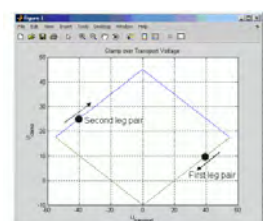
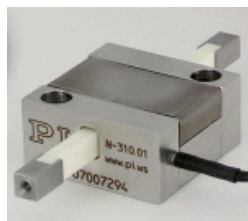


PZ205E User Manual
E-861 NEXACT® Controller
Release: 1.2.1 Date: 26 July 2010



This document describes the following product:

- E-861.1A1
NEXACT® Controller, 1 channel, linear encoder



Declaration of Conformity

according to DIN EN ISO/IEC 17050:2005-01

Manufacturer:	Physik Instrumente (PI) GmbH & Co. KG	
Manufacturer's Address:	Auf der Römerstrasse 1 D-76228 Karlsruhe, Germany	

The manufacturer hereby declares that the product

Product Name: **NEXACT® Controller**

Model Numbers: **E-861**

Product Options: **all**

complies with the following European directives:

2006/95/EC, Low voltage directive (LVD)

2004/108/EC, EMC-Directive

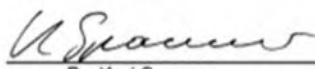
The applied standards certifying the conformity are listed below.

Electromagnetic Emission: EN 61000-6-3, EN 55011

Electromagnetic Immunity: EN 61000-6-1

Safety (Low Voltage Directive): EN 61010-1

November 03, 2008
Karlsruhe, Germany


Dr. Karl Spanner
President

About This Document

Users of this Manual

This manual is designed to help the reader to operate the E-861 NEXACT® Controller. It assumes that the reader has a fundamental understanding of basic servo systems, as well as motion control concepts and applicable safety procedures.

The manual describes the physical specifications and dimensions of the E-861 as well as the software and hardware installation procedures and the commands which are required to put the associated motion system into operation.

Conventions

The notes and symbols used in this manual have the following meanings:



WARNING

Calls attention to a procedure, practice or condition which, if not correctly performed or adhered to, could result in injury or death.



CAUTION

Calls attention to a procedure, practice, or condition which, if not correctly performed or adhered to, could result in damage to equipment.

NOTE

Provides additional information or application hints.

The software tools and the mechanics which might be mentioned within this documentation are described in their own manuals. All documents are available as PDF files. Updated releases are available for download at www.pi.ws (<http://www.pi.ws>) or via email: contact your Physik Instrumente Sales Engineer or write info@pi.ws (<mailto:info@pi.ws>).

Related Documents

E861_GCSLabVIEW_PZ208E E-861_PIGCS_2_0_DLL_SM152E IP1000_B_EN.pdf (GEMAC interpolation chip)	PIMikroMoveUserManual_SM148E GCSDData_User_SM146E PiStageEditor_SM144E
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All documents are available as PDF files on the distribution CD. Updated releases are available for download at www.pi.ws or via email: contact your Physik Instrumente sales engineer or write info@pi.ws.

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Subject to change without notice. This manual is superseded by any new release. The newest release
is available for download at www.pi.ws (<http://www.pi.ws>).

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1 Introduction

The E-861 NEXACT® controller is designed to drive a single-axis PiezoWalk® system with NEXACT® linear drive in open-loop or closed-loop operation. NEXACT® PiezoWalk® technology overcomes the limitations of conventional nanopositioning drives and combines virtually unlimited travel ranges with high stiffness in a very small package. Furthermore, NEXACT® linear drives provide piezo class resolution (far below one nanometer) and millisecond responsiveness. The special drive design also reduces the operating voltage to 45 V and below.

Two motion modes are provided: To move the runner over longer distances a "nanostepping mode" is used, whereas for distances smaller than one step, the "analog mode" enables high-dynamics positioning with resolutions far below one nanometer. According to the desired motion modes, the E-861 NEXACT® controller performs coordinated control of the four voltage channels required for the NEXACT® linear drive.

Communication with the E-861 is provided either through the RS-232 or the USB interface. For manual control, the unit can be operated with a joystick.

Flexible Automation

The E-861 NEXACT® Controller offers a number of features to facilitate automation and handling tasks in research and industry. For example, macros can be stored in the non-volatile memory for later recall. Stand-alone capability is provided by a user-programmable autostart macro to run automation tasks at power-up (no run-time computer communication required!).

For easy synchronization of motion with internal or external trigger signals four input and four output lines are provided.

Multi-Axis Control

Up to 16 E-861 NEXACT® Controllers can be daisy-chained and addressed via the same interface.

The networking feature allows the user to start out with one controller and add more units later for multi-axis setups.

Command Set

E-861 NEXACT® Controllers can be operated using the PI General Command Set (GCS). PI-GCS allows networking of different controller units, both for piezo-based and motorized positioning units, with minimal programming effort.

Software / Programming

In addition to the user software for setup, system optimization and operation, comprehensive LabVIEW and DLL libraries are provided to ease programming custom applications.

1.1 Prescribed Use

Based on their design and realization, E-861 NEXACT® Controller are intended to drive capacitive loads, in the present case, piezoceramic actuators. E-861s must not be used for applications other than stated in this manual, especially not for driving ohmic (resistive) or inductive loads. Observe the safety precautions given in this User Manual.

E-861s can be operated in closed-loop mode using incremental position sensors. Consult the product specifications of the mechanics with which the E-861 is to be operated to see what kind of position sensor is present.

The E-861 may only be used for applications suitable according to the device specifications. Operation other than instructed in this User Manual may affect the safeguards provided.

The verification of the technical specifications by the manufacturer does not imply the validation of complete applications. In fact the operator is responsible for the process validation and the appropriate releases.

The E-861 is a laboratory apparatus as defined by DIN EN 61010. It meets the following minimum specifications for safe operation:

- Indoor use only
- Altitude up to 2000 m
- Temperature range 5°C to 40°C
- Max. relative humidity 80% for temperatures up to 31°C, decreasing linearly to 50% relative humidity at 40°C
- Line voltage fluctuations not greater than $\pm 10\%$ of the line voltage
- Transient overvoltages as typical for public power supply
Note: The nominal level of the transient overvoltage is the standing surge voltage according to the overvoltage category II (IEC 60364-4-443).
- Degree of pollution: 2

These data are no limitations for the specifications in the technical data table.

1.2 Safety Precautions

Controller

DANGER

Procedures which require opening the case should be carried out by authorized, qualified personnel only.

Disconnect the controller from power when opening the case, and when resetting internal switches or jumpers.

When the controller must be operated with the case open, voltages of up to 48 VDC and currents of up to 2 A can be exposed. Do not touch internal conductors.



WARNING—READ INSTRUCTION

Install and operate the E-861 NEXACT® Controller only when you have read the operating instruction. Keep the instructions readily available close to the device in a safe place. If the instructions are lost or have become unusable, ask the manufacturer for a new copy. Add all information given by the manufacturer to the instructions, e.g. supplements or Technical Notes.



WARNING

Connect the AC power cord of the external power supply to the wall socket (100 to 240 VAC).

To disconnect the system from the supply voltage completely, remove the power plug from the wall socket.

Install the system near the AC outlet and such that the AC power plug can be reached easily.



WARNING

All motion of the connected motors is software controlled, and software may fail. Defective software or improper operation of the software may result in unexpected motions. Be aware that some motorized positioners can generate large forces which can cause personal injury or other damage if not properly handled.





CAUTION

Place the system in a location with adequate ventilation to prevent internal heat build-up. Allow at least 10 cm (4 inches) clearance from the top and the rear of the unit and 5 cm (2 inches) from each side.



CAUTION

Never connect the RS-232-IN and USB connectors of the same controller to a PC at the same time as this can cause damage to the controller.



CAUTION

If no sensor is present in your system:

- Do not switch servo on (SVO command)
- Do not send commands for closed-loop motion, like MOV or MVR
- Do not send the open-loop commands OMA and OMR, since they use a sensor, too

Otherwise the connected mechanics can run into the hard stop at full speed, which may cause damage to your hardware setup.



CAUTION

Incorrect E-861 parameter values may lead to improper operation or damage of your hardware. Be careful when changing parameters.



CAUTION

The E-861 is equipped with a watchdog timer. This safety device resets the E-861 in case of software failure.



CAUTION

Do not enable a joystick via command when no joystick device is connected to the controller hardware. Otherwise the corresponding controller axis may start moving and could damage your application setup.

CAUTION

The boards inside the E-861 are ESD-sensitive (electrostatic discharge sensitive) devices. Observe all precautions against static charge buildup before handling these devices. Avoid touching circuit components, pins and PCB traces. Discharge any static electricity you may have on your body by briefly touching a conductive, grounded object before you touch any electronic assembly.

Make sure that no conductive particles of any kind (metallic dust or shavings, broken pencil leads, loose screws) contact the device circuitry.

Mechanics

CAUTION

Do not displace the moving platform of a NEXACT® stage or the runner of a NEXACT® linear drive manually! Manual displacement can cause irreparable damage to the piezo modules in the NEXACT® linear drives.

1.3 Unpacking

Unpack the E-861 NEXACT® Controller with care. Compare the contents against the items covered by the contract and against the packing list.

The following components are included:

- NEXACT® Controller (E-861.1A1)
- Power Supply 24 V, 42 W (C-663.PS), with line cord (3763)
- RS-232 null-modem cable for connecting controller and host PC (C-815.34)
- RS-232 straight-through networking cable (C-862.CN) for daisy chain
- USB cable (3 m, USB-A (m) / USB Mini-B (m)) for PC connection (000014651) and EMI-suppression ferrite (000015165)
- E-861 Distribution CD, containing host software (see "Software Overview" (p. 10)), USB driver and manuals as PDF files (E-861.CD)
- User Manual for E-861 in printed form (this document)

If parts are missing or you notice signs of damage, contact your PI representative or write to info@pi.ws immediately.

Save all packing materials in case the product needs to be shipped again.

1.4 Additional Components

Contact your PI representative or write an e-mail to info@pi.ws if you need the following additional components:

Order Number	Description
C-862.CN2	Long straight-through networking cable for daisy chain (interconnecting E-861 controllers on RS-232 bus), 180 cm
C-819.20	Analog joystick, 2 axes
C-819.20Y	Y-cable for connecting two E-861s to joystick
C-170.PB	Pushbutton box with 4 buttons and 4 LEDs, for connection to the I/O socket (p. 218)
C-170.IO	Connector for I/O socket (p. 218), with cable, open end

1.5 Motion System Requirements

To start working with the E-861 NEXACT® controller, your motion system must include the following components:

- Power supply for E-861
- The mechanics (NEXACT® linear drive or stage)
- A PC with Windows operating system (XP, Vista, 7.0)
- Communication interface to the PC:
A free COM port on the PC or
A free USB interface on the PC
- RS-232 null modem cable or USB cable to connect controller and host PC
- E-861 CD with host software

1.6 Software Description

The table below lists the software tools which are on the E-861 product CD with application recommendations.

For more information see the corresponding software manuals.

Software Tool	Supported Operating System	Short Description	Recommended for
PI Terminal	Windows	PI Terminal is a Windows GUI which can be used as a simple terminal with almost all PI controllers.	Users who want to send the commands of the PI General Command Set (GCS) directly.
GCS Library	Windows	Allows program access to the E-861 from languages like C++. The functions in the library are based on the PI General Command Set (GCS). Windows operating systems: PI_GCS2_DLL	Customers who want to use a library for their applications. The dynamic version of the library is needed by the LabVIEW driver set and by PIMikroMove.
LabVIEW drivers	Windows	LabVIEW is a software tool (available separately from National Instruments) for data acquisition and process control. The E-861 LabVIEW software consists of a collection of virtual instrument (VI) drivers for the E-861 controller. This driver set supports the PI General Command Set (GCS). Included are VIs for GCS commands and high-level VIs for various tasks.	Users who want to use LabVIEW for programming their applications based on the GCS. See the GCS LabVIEW manual of your controller for more information.
PIMikroMove	Windows	PIMikroMove permits you to start your motion system—host PC, controller and stage(s)—immediately without the need to write customized software. It offers motion-control displays and features that in many cases make it unnecessary to deal with ASCII-format commands. It also has a complete command input facility, which represents an easy way to experiment with various commands. PIMikroMove uses the GCS DLL described above to command the controller. Note that the program offers comprehensive online support.	Users who want to test the equipment before or instead of programming an application and who want to learn how to use the commands. For motor controllers, PIMikroMove offers an easy way to optimize the servo parameters.
PIStageEditor	Windows	GUI tool for adding, removing and editing stages (parameter sets) in stage-parameter files (DAT-files) used by the GCS library and the other host software from PI	Users who want to check or edit the content of the stage databases used by the host software

TMS320F28xx Updater	Windows	The TMS320F28xx Updater firmware update program guides you through the update of the firmware for your E-861 system.	Users who want to update the firmware.
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2 First Steps

2.1 Requirements for Closed-Loop Operation and Custom Systems

Before you start with closed-loop operation make sure that the set controller parameters match:

- a) the properties of the mechanics
- b) the properties of the sensor used for position feedback
- c) your individual application

If you use a custom stage you can use the Default-Stage-N stage database entry. This stage database entry contains parameter settings that you may have to adjust to match with your stage's properties.

See "Default-Stage-N Parameter Settings" (p. 49) for the parameter settings the Default-Stage-N stage database entry features.

See "Customizing the System" (p. 89) for what parameters may need to be adjusted.

See "How to Store Parameter Settings" (p. 37) for how to store parameters to volatile and non-volatile memory.

In addition you have to check if the sensor properties of your custom stage match with the GEMAC parameters reflecting the sensor properties.

Note that the GEMAC parameters are not part of a stage database entry.

See "GEMAC Parameters" (p. 105) and "Adjustment for Custom Sensor" (p. 99) for details.

2.2 Getting Started

To simplify your first steps with the NEXACT® system, it is recommended to use PIMikroMove (see the PIMikroMove Manual for more information).

CAUTION

Never connect the RS-232-IN and USB connectors of the same controller to a PC at the same time as this can cause damage to the controller.





CAUTION

If no sensor is present in your system, do not switch the servo on. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

NOTE

It is recommended to check the parameter settings on the controller before a stage database entry is chosen during setting up a connection with PIMikroMove.

If the parameter settings must not be changed, then press OK (instead of *Assign -->*) in the *Select connected stages* step, see figure of step 9b) below.

It is possible to generate user-defined stage database entries. See "How to Create a New Stage Type in the PI Stages Database" (p. 98) for how to generate a new parameter set (= stage database entry). Such a user-defined stage database entry will be available in PIMikroMove in the *Select connected stages* step.

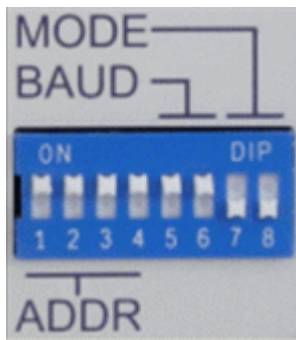
See "Storing Parameter Settings to Non-Volatile Memory Using PIMikroMove Main Window" (p. 38) if you wish to store these settings to the controller's non-volatile memory to make them power-up default settings.

To start operation with the E-861 proceed as described below.

Note that closed-loop operation is only possible if your system features a sensor.

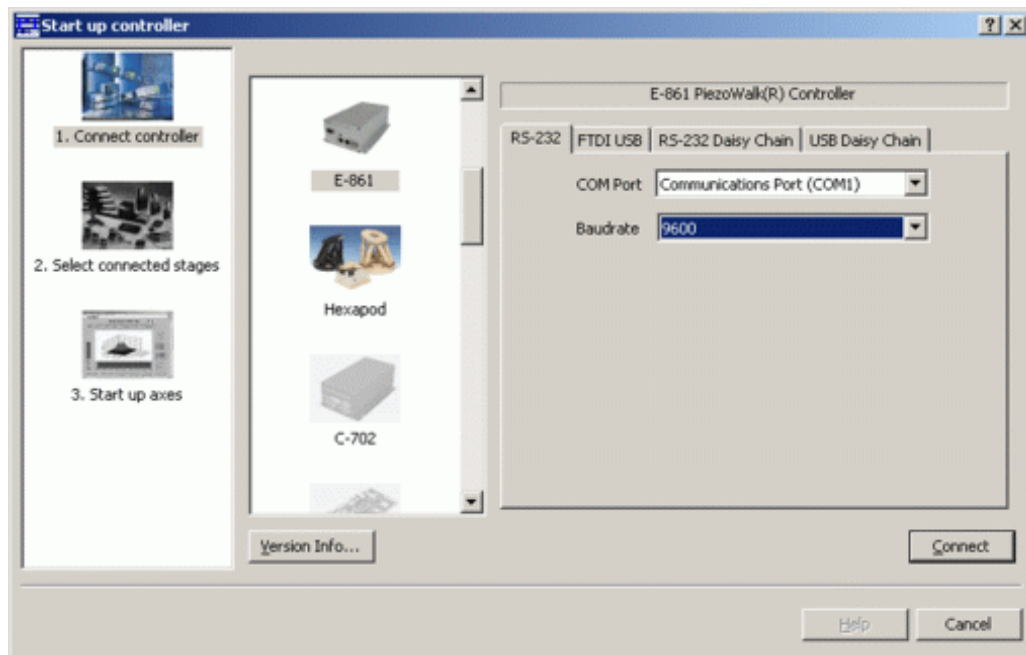
- 1 Connect the NEXACT® stage to the "Motor" socket on the rear of the E-861.
- 2 If present, connect the NEXACT® stage to the "Sensor" connector on the rear of the of the E-861.
- 3 Starting operation for the first time, you should use the default DIP switch settings of the E-861 which are as shown in the figure below:

Controller address = 1
Baudrate = 9600 baud
Mode = Normal operation



If you want to change the default settings, see "DIP Switch Settings" for details.

- 4 Connect the E-861 to the host PC.
Use either the RS-232 interface (via the "RS-232 In" socket on the controller) or the USB interface and the corresponding cable which is included in delivery.
Never connect both interfaces at the same time.
- 5 Connect E-861 and the included 24 VDC wide-range power supply (use the "24 VDC" socket on the E-861 rear panel).
- 6 Connect the power supply of the E-861 to the line power (100-240 VAC).
The controller is powered on and immediately ready for operation (STA LED lights up permanently).
- 7 Start PIMikroMove on the host PC.
See "Installing the Software on the Host PC" (p. 27) for installation.
- 8 Establish a connection to the E-861 controller from PIMikroMove.
 - a) Select the E-861 controller in the *Start up controller* window, see figure below.



This figure shows the *Start up controller* window at the *Connect controller* step.

Here, the E-861 is physically connected via RS-232. 9600 baud is the factory default baud rate setting.

The controller has address 1 as is determined by DIP switch settings at the controller's front panel.

b) Depending on the physical connection select the *RS-232*, *FTDI USB*, *RS-232 Daisy Chain* or *USB Daisy Chain* tab card in the *Start up controller* window.

When using the USB interface for the first time, two FTDI USB drivers must be installed on the host PC. These drivers are provided on the E-861 CD in the \USB Driver directory.

Note that with a daisy-chain there must be one controller with address 1. It is not required that this controller is directly connected to the host PC, i.e. this controller does not have to be the first controller of the daisy-chain.

If there is no controller in a daisy-chain with address 1 an error message occurs when you try to setup a connection.

See "Connecting Controller or Daisy-Chain Network to Host PC" (p. 27) for detailed information.

c) For RS-232 connection choose the baud rate as preset by the DIP switch settings at the controller's front panel.

d) Press *Connect* in the *Start up controller* window to establish the connection.

9 Choose the stage type to be connected.

Click *Select connected stages* on the E-861 menu of the PIMikroMove

main window if the stage selection dialog for the next step does not open automatically.

There are the following possibilities:

- a) The preset *Current stage type* in the *Controller axes* pane does not match your stage.
- b) The preset *Current stage type* does match your stage.

Details:

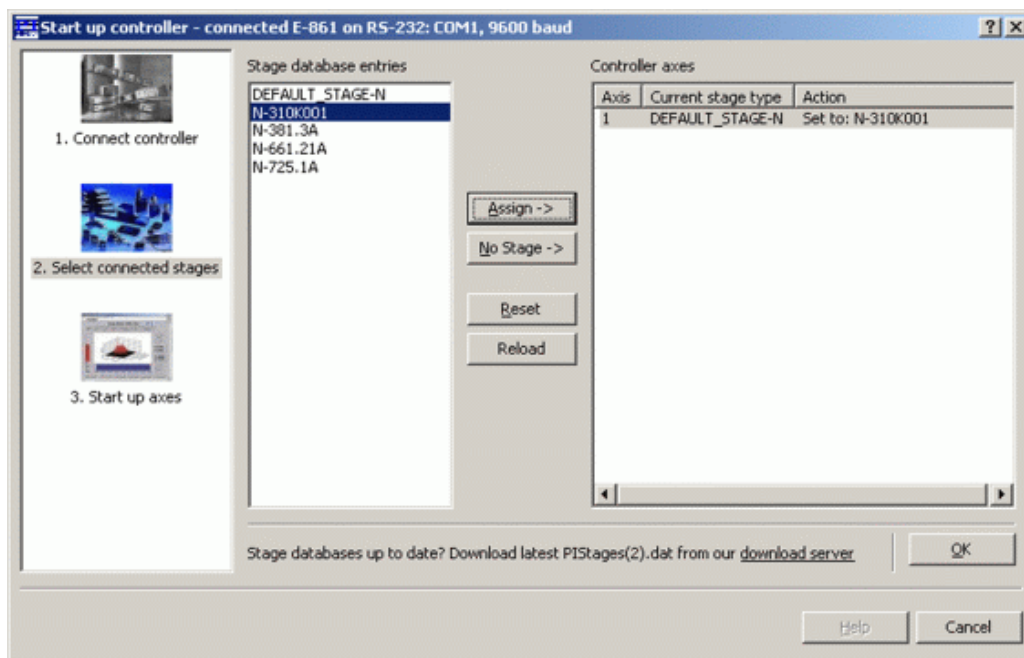
- a) If the preset stage type is not to be used select the appropriate stage type in the *Stage database entries* list and press the *Assign ->* button for each axis.

The selected stage types are now visible in the *Controller axes* pane.

Set to: stage name occurs in the *Action* column, see figure below.

To accept the selection and to close the dialog, press the *OK* button.

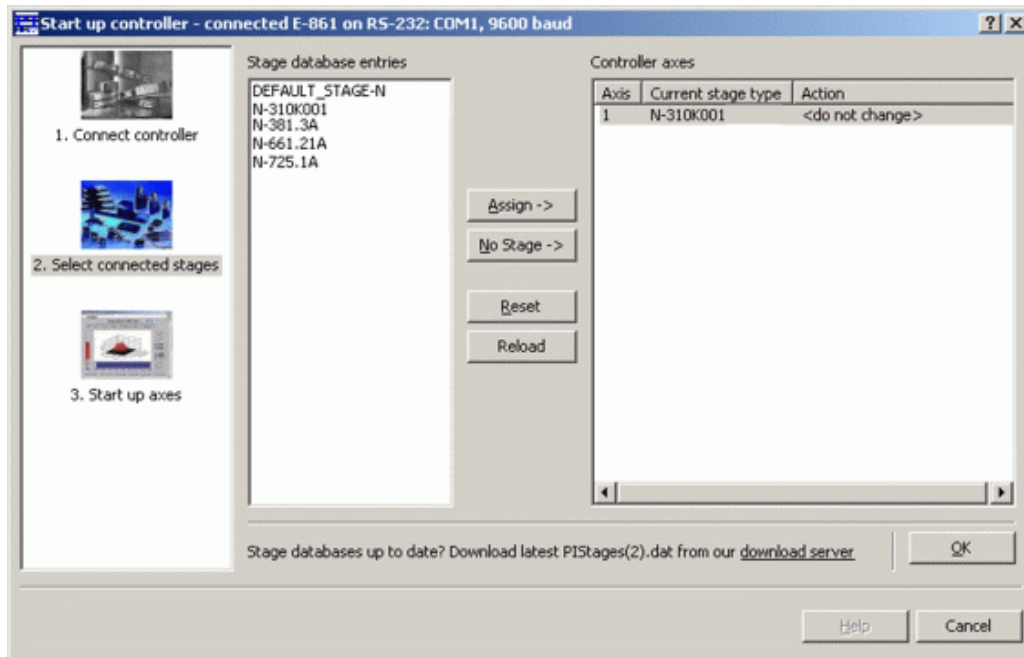
The figure below shows the *Start up controller* window with the *Select connected stages* step. Here a stage database entry for a specific stage is chosen.



If you wish to store the settings you chose as power-up default settings to the controller's non-volatile memory see "Storing Parameter Settings to Non-Volatile Memory Using PIMikroMove Main Window" (p. 38) for instructions.

- b) If a connection is started *<do not change>* occurs automatically in the *Action* column, see figure below.

Then, if the preset stage type is to be used accept the preset stage database entry by pressing the *OK* button.



If your stage features a sensor, go on with step 10 to reference the axis.

If your stage does not feature a sensor, proceed with step 11a) to command motion.

Notes:

While choosing the stage type, the parameters for that stage type will be loaded automatically from a stage database on the host PC to the controller's volatile memory.

Make sure that you always have installed the latest version of the PISTages2.dat stage database. See "Installing the Software on the Host PC" (p. 27) and "Updating PISTages2.dat" (p. 32) for details.

The choice can later be changed with *Select connected stages* on the E-861 menu in the PIMikroMove main window.

See "Controller Parameters" (p. 35) and "Customizing the System" (p. 89) for more information regarding parameter settings.

10 Start reference moves for the axes.

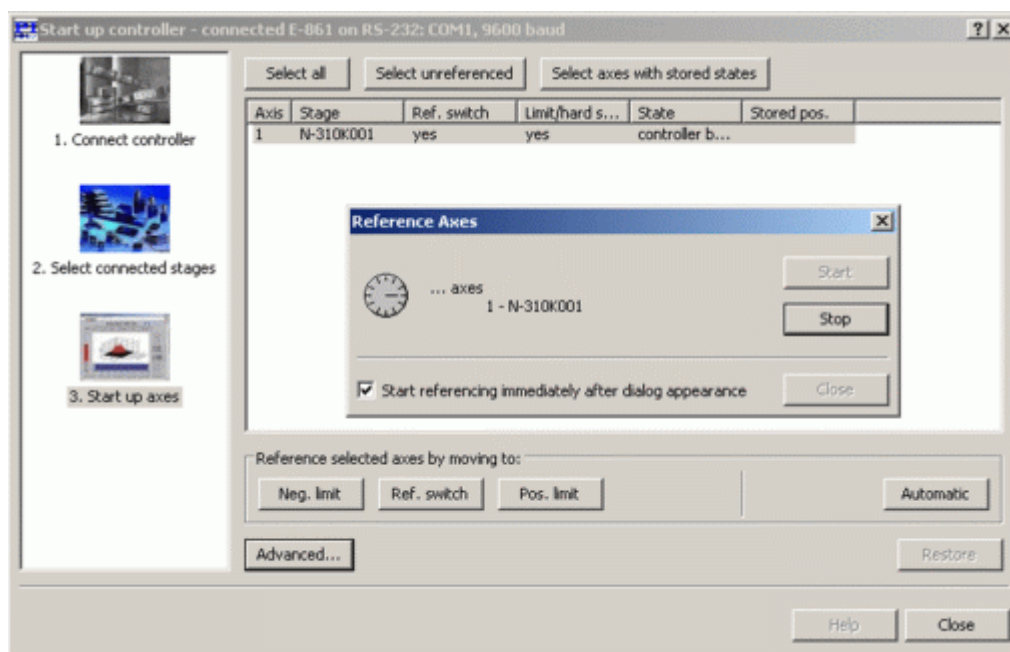
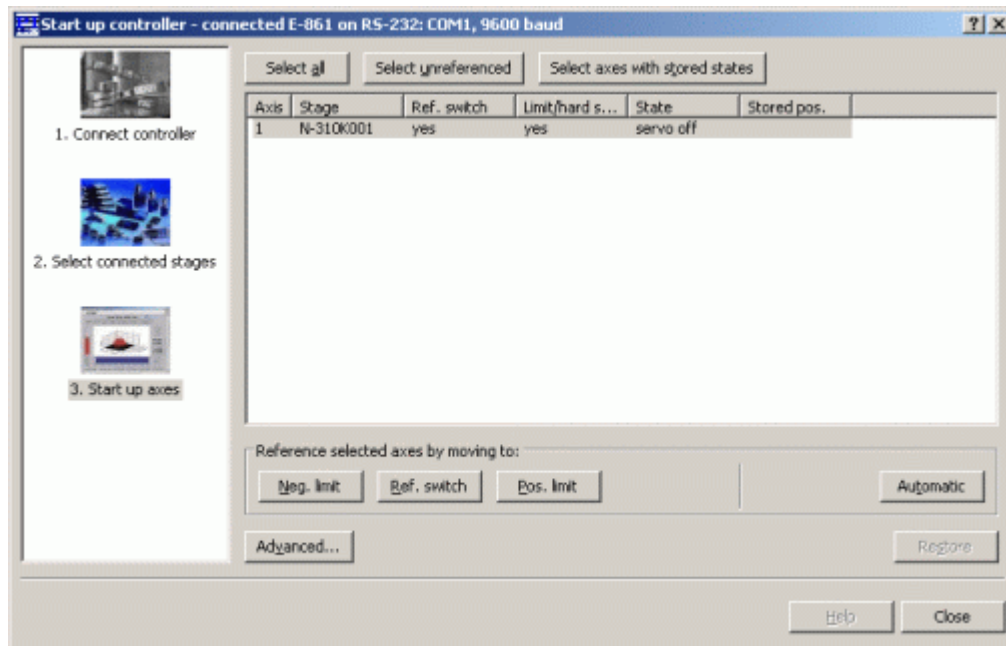
Note that this step can only be performed if your mechanics features a sensor and reference or limit switches. In addition, the relevant parameters have to be enabled accordingly.

With Default-Stage-N parameter settings reference or limit switches are disabled. Thus referencing is not possible with this parameter set.

Due to the nature of the incremental sensors used in the stages, the

controller cannot know the absolute position of an axis upon startup. Reference and/or limit switches in the stage can be used to obtain absolute position information.

The figures below show the *Start up controller* window with the *Start up axes* step. Click *Automatic* to start the reference move.



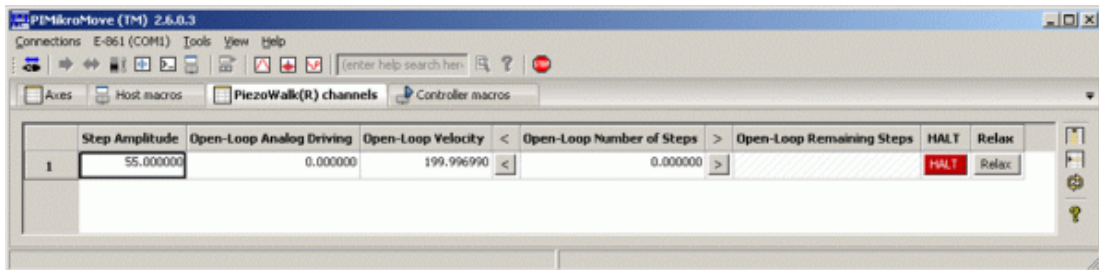
When referencing is successfully finished, press the *Close* button. The PIMikroMove main window will open. See "Referencing" (p. 51) for more information.

11 Start some test moves of the axis. Depending on your settings there are the following possibilities:

a) Mechanics does not feature a sensor:

Select the *PiezoWalk (R) channels* tab in the PIMikroMove main window, see figure below.

Insert an appropriate value in the *Open-Loop Number of Steps* field. To exert motion press the associated arrow buttons.



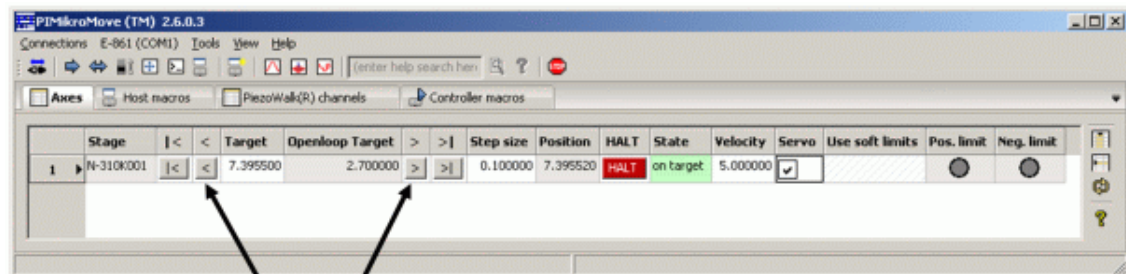
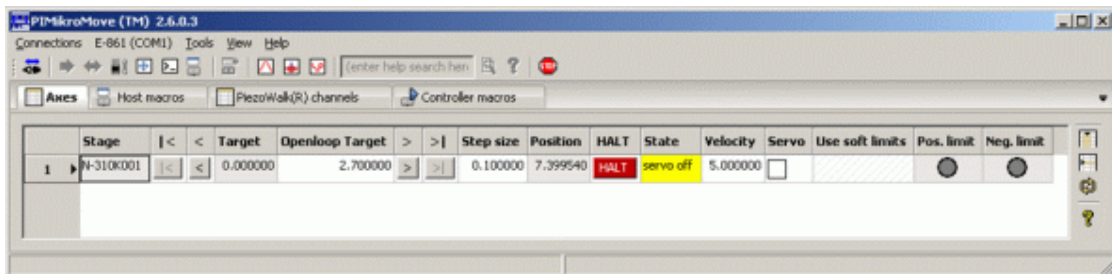
b) Mechancis features a sensor:

Select the *Axes* tab in the PIMikroMove main window, see figures below.

You can command motion either in open-loop or closed-loop operation.

Activate servo to command motion in closed-loop operation.

For example, perform a step of a predefined size by pressing the associated arrow buttons for an axis



Arrows causing motion

For how to realize stand-alone operation see "Preparing for Stand-Alone Operation" (p. 85).

See "Working with Controller Macros" (p. 82) for how to store macros in the E-861's non-volatile memory for later recall and "Joystick Control" (p. 79) for manual control by a joystick connected to the E-861.

2.3 Example for Commanding Motion

CAUTION

If no sensor is present in your system:

- Do not switch servo on (SVO command)
- Do not send commands for closed-loop motion, like MOV or MVR
- Do not send the open-loop commands OMA and OMR, since they use a sensor, too

Otherwise the connected mechanics can run into the hard stop at full speed, which may cause damage to your hardware setup.

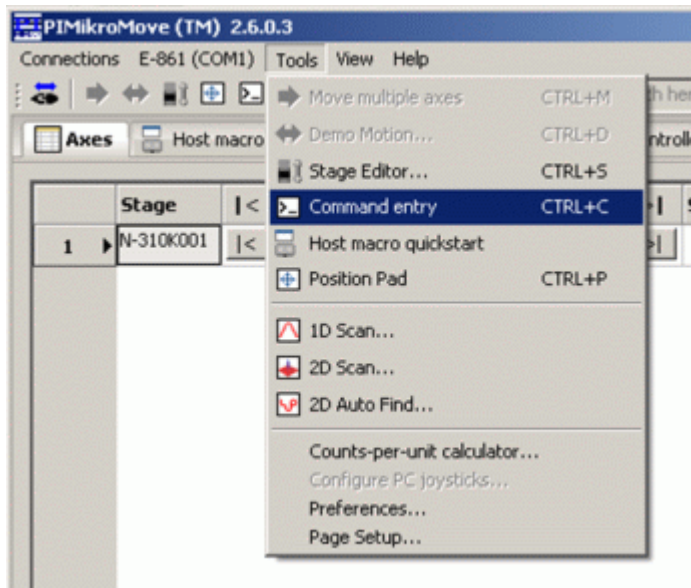
After setting up a connection with PIMikroMove you can perform some test motion.

Note that your stage must feature a sensor to reference and to perform closed-loop motion. The example described below requires that your system features a sensor.

Proceed as follows:

- 1 Reference and activate servo first, see steps 10 and step 11 in "Getting Started" (p. 12) for details.
Note that your stage must feature a sensor to reference and to perform closed-loop motion.
- 2 To send the commands as given below follow the *Tools* → *Command entry* menu sequence in the PIMikroMove main window, see figure below.





- 3 Then you can send motion commands via the *Command entry* window as listed in the example given below.

The example below shows how to perform closed-loop and open-loop motion. See "Modes of Operation" (p. 54) for more information regarding the motion modes of a NEXACT® linear stage and the transitions between them.

MOV 1 6	Closed-loop motion, Axis 1 moves to absolute position 6 mm. Note that motion can be performed either only in nanostepping mode or in an alternating sequence of nanostepping and analog motion. See "Motion Modes" (p. 56) for details.
MVR 1 -5	Closed-loop motion, moves Axis 1 relative to the last commanded closed-loop target position.
SVO 1 0	Servo must be disabled to enable open-loop commands. Disabling servo includes an automatic <i>Relaxing</i> procedure. (See also "Changing Motion and Servo Mode" (p. 59) for details) Therefore, a motion in analog mode can be performed by a next OAD command.
OAD 1 40	Open-loop analog motion of PiezoWalk channel 1, set feed voltage to +40 volts which corresponds to a motion of approx. 3.3 μm , depending on stage, load and motion direction, in positive direction.
RNP 1	<i>Relaxing</i> brings the PiezoWalk channel 1 to a full-holding-force, zero-drive voltage <i>Relaxed</i> state, is required before the motion mode can be changed from analog to nanostepping motion in open-loop operation (and vice versa), and before servo is activated for closed-loop operation.
SVO 1 1	Servo is activated.
MOV 1 5	Closed-loop motion, Axis 1 moves to absolute position 5 mm.

SVO 1 0	Servo must be disabled to enable open-loop commands. Disabling servo includes an automatic <i>Relaxing</i> procedure.
OAD 1 -20	Open-loop analog motion of PiezoWalk channel 1, set feed voltage to -20 volts which corresponds to a motion of approx. 1 μm , depending on stage, load and motion direction, in negative direction.
RNP 1	<i>Relaxing</i> of PiezoWalk channel 1 is required to prepare stage for nanostepping motion.
SSA 1 40	Voltage amplitude for nanostepping motion is set to +40 volts.
OSM 1 100	Open-loop nanostepping motion, PiezoWalk channel 1 moves 100 steps in positive direction.
OMA 1 6	Open-loop nanostepping motion, Axis 1 moves to absolute position, i.e. to absolute position of approximately 6 mm.
OMR 1 -3	Open-loop nanostepping motion, moves Axis 1 relative to the last commanded open-loop target position, here by 3 mm in negative direction.
RNP 1	<i>Relaxing</i> of PiezoWalk channel 1 is required to prepare stage for analog motion.
OAD 1 -40	Open-loop analog motion of PiezoWalk channel 1, set feed voltage to -40 volts which corresponds to a motion of approx. 3.3 μm , depending on stage, load and motion direction, in negative direction.

3 Details of Operation

3.1 Front and Rear Panel Elements

3.1.1 Front Panel Elements

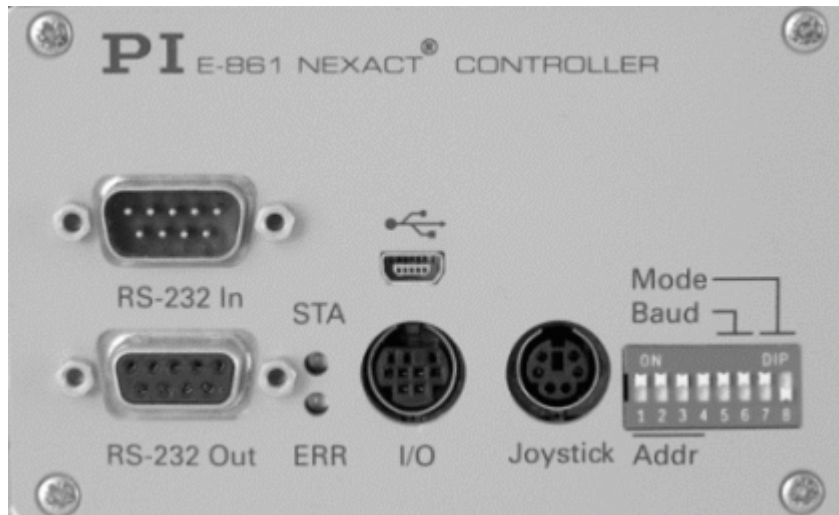



Figure 1: Front Panel of E-861.1A1

Name	Function
RS-232 In	Serial connection to host PC or to previous controller in a daisy-chain network. See "RS-232 In and RS-232 Out Sockets" (p. 216) for pinout.
RS-232 Out	Serial connection to next controller in a daisy-chain network. See "RS-232 In and RS-232 Out Sockets" (p. 216) for pinout.
STA LED (green)	Power on and ready indicator. When power is applied to the controller, the LED will glow for normal operation.
ERR LED (red)	Error indicator; when LED lights up, error code is non-zero and can be queried and cleared using the ERR? command (p. 127).
	Universal Serial Bus (USB) for connection to host PC. See "USB Socket" (p. 217) for more information.
I/O	Mini DIN 9-pin connector, provides digital I/O and analog input lines. See "I/O Socket" (p. 218) for pinout.
Joystick	Mini DIN 6-pin connector for analog joystick (input). See "Joystick Socket" (p. 220) for pinout.

Name	Function
Mode, Baud, Addr	8-bit DIP switch, sets controller address, RS-232 baud rate and operating mode of unit. See "DIP Switch Settings" for details.

3.1.2 DIP Switch Settings

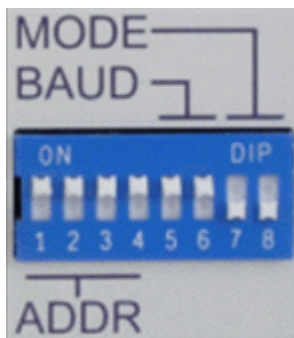


Figure 2: Slider up = ON, slider down = OFF

Name	Function
Addr (switch 1 to 4)	Controller address (1 to 16)
Baud (switch 5 and 6)	Baud rate (9600, 19200, 38400 or 115200**)
Mode (switch 7 and 8)	Operating mode (normal operation or firmware update)

** older firmware revisions may not support 115200 baud

Factory settings are shown in bold in the following tables.

Address	SW1	SW2	SW3	SW4
1	ON	ON	ON	ON
2	ON	ON	ON	OFF
3	ON	ON	OFF	ON
4	ON	ON	OFF	OFF
5	ON	OFF	ON	ON
6	ON	OFF	ON	OFF
7	ON	OFF	OFF	ON
8	ON	OFF	OFF	OFF
9	OFF	ON	ON	ON
10	OFF	ON	ON	OFF
11	OFF	ON	OFF	ON
12	OFF	ON	OFF	OFF
13	OFF	OFF	ON	ON
14	OFF	OFF	ON	OFF
15	OFF	OFF	OFF	ON
16	OFF	OFF	OFF	OFF

Baud Rate*	SW5	SW6
9600	ON	ON
19200	ON	OFF
38400	OFF	ON
115200**	OFF	OFF

*Other settings are fixed at 8 data, 1 stop, no parity; Internal buffers are used so there is no handshake required

**Older firmware revisions may not support 115200 baud

Mode	SW7	SW8
Firmware update	OFF	ON
Normal	OFF	OFF

3.1.3 Rear Panel Elements

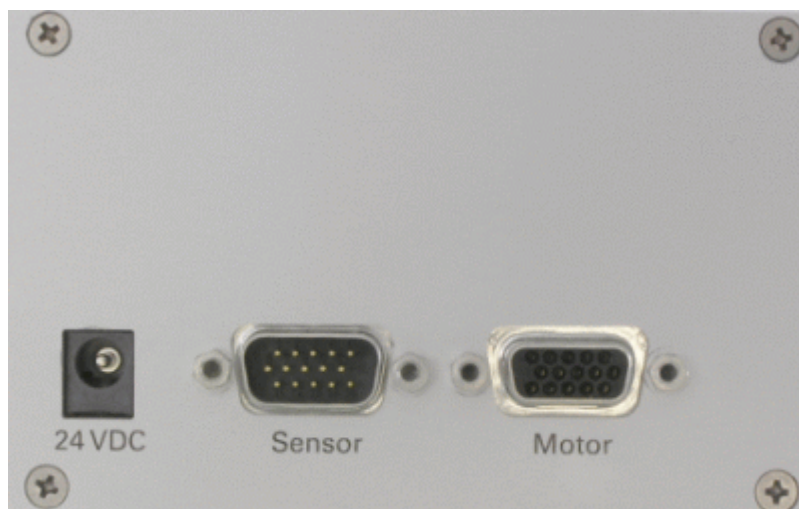


Figure 3: Rear Panel of E-861.1A1

Name	Function
24 VDC	Connector for power supply. See "24 VDC Socket" (p. 221) for pinout.
Sensor	Sub-D connector for position feedback devices such as an incremental encoder and for the signals of limit and reference sensors. See "Sensor Socket" (p. 216) for pinout.
Motor	Sub-D connector for NEXACT® drive. See "Motor Socket" (p. 215) for pinout.

3.2 Installing the E-861

The E-861 can be used as desktop device or mounted on a base in any orientation. If you want to mount the E-861 on a base, see "Mounting Hole Pattern" (p. 214).

CAUTION


Place the system in a location with adequate ventilation to prevent internal heat build-up. Allow at least 10 cm (4 inches) clearance from the top and the rear of the unit and 5 cm (2 inches) from each side.

!

Because grounding is not assured over the power connection, the E-861 chassis must be connected to a protective ground, e.g. via one of the fixing screws on the front or rear panel.

3.3 Installing the Software on the Host PC

Windows operating systems:

- 1 Insert the E-861 CD in your host PC.
- 2 If the Setup Wizard does not open automatically, start it from the root directory of the CD with the  icon.
- 3 Follow the on-screen instructions and select the “typical” installation. Typical components are LabVIEW drivers, GCS DLL, PIMikroMove.

For an overview over the host software provided see "Software Description" (p. 10).

3.4 Connecting Controller or Daisy-Chain Network to Host PC



CAUTION

Never connect the RS-232-IN and USB connectors of the same controller to a PC at the same time as this can cause damage to the controller.

Use either the RS-232 or the USB interface to connect the E-861 or an E-861 daisy chain network to the host PC.

Up to 16 E-861 controllers can be controlled from a single host computer interface. The RS-232 output stages of some PCs may not be capable of driving more than 6 units; if this is a problem use USB to interface with the PC.

Interconnect any additional controllers being networked to the network with straight-through RS-232 cables chaining off the RS-232 OUT connector of the controller connected to the PC (one straight-through RS-232 cable (C-862.CN) comes with each E-861 controller).

NOTES

In a daisy-chain, connected via USB or via RS-232, there must be one controller with address 1. It is not required that this controller is directly

connected to the host PC, i.e. this controller does not have to be the first controller of the daisy-chain.

If there is no controller in a daisy-chain with address 1 an error message occurs when you try to setup a connection.

3.4.1 USB Interface

The first time you connect over the USB interface, be sure you are logged on the PC as a user having administrator rights. After the E-861 is powered on, a message will appear saying that new hardware has been detected. Follow the on-screen instructions and insert the E-861 CD again. The required hardware drivers are found in the \USB Driver directory.

The USB drivers will make the USB interface appear to all software on the host PC as a new COM port. That port will be present only when the controller is connected via USB and powered on. Depending on the way the connection between E-861 and host PC is established in the host software, it may be possible to select the baud rate of that PC COM port. Make sure that the selection corresponds to the baud rate settings of the E-861 (made via the DIP switches on the E-861 front panel).

3.4.2 Baud Rate Settings

The baud rate can be set to one of 9600, 19200, 38400 and 115200 using the Baud DIP switches on the E-861 front panel, see "DIP Switch Settings" for details (115200 may not be supported by older firmware revisions). All controllers in a daisy chain network must be set to the same baud rate. Other communication settings are fixed at 8 data, 1 stop, no parity; internal buffers are used so there is no handshake required.

3.4.3 Address Settings

The controller address of the E-861 can be set with the Addr DIP switches on the front panel, see "DIP Switch Settings" for details. Possible controller addresses are in the range of 1 to 16, address 1 is default. The host PC always has the address 0.

See "Target and Sender Address" (p. 110) for more information about the format of the command line.

In a daisy chain network, each E-861 must have a unique controller address and one controller of the daisy-chain must have address 1. See also "Connecting Controller or Daisy-Chain Network to Host PC" (p. 27) for more information.

The communication on the interface is between the host computer and a specifically addressed controller in the chain. With the broadcast address 255, all controllers can be addressed at the same time, but no reports are displayed on the host PC.

NOTES

Except when making the required hardware settings, you have to deal with addresses only if the connection between E-861 and host PC is done via a terminal program without any intervening software layers (e.g. DLLs). With PITerminal, this is the case if the connection is made by pressing the *Connect...* button.

3.5 Referencing

Because the encoder signals used for position feedback provide only relative motion information, the controller cannot know the absolute position of an axis upon startup. This is why a referencing procedure is required before absolute target positions can be commanded and reached.

For the implementation of the referencing functionality in the individual host software components, see the appropriate manuals.

3.5.1 Reference Mode

The current reference mode setting of the controller (ask with RON? (p. 170)) determines how referencing can be performed. By default, a reference move must be performed (p. 30), but it is also possible to set absolute positions manually (p. 30). To switch between the two reference modes, use the RON command (p. 170).

3.5.2 Perform a Reference Move

When the reference mode is set to "1" (factory default), referencing is done by performing a reference move with FRF (p. 133), FPL (p. 131) or FNL (p. 129).

NOTES

Neither relative nor absolute targets can be commanded as long as referencing was not successfully performed.

FRF requires that the axis has a reference switch (ask with TRS? (p. 188)), and FPL and FNL require that the axis has limit switches (ask with LIM? (p. 146)). The limit switches can only be used for reference moves if the travel range is not reduced by soft limits, see "Travel Range Adjustment" (p. 92) for more information.

For best repeatability, always reference in the same way.

The FRF command always approaches the reference switch from the same side, no matter where the axis is when it is issued.

3.5.3 Set Absolute Position

When the reference mode is set to "0", referencing is done by entering an absolute position value using the POS command (p. 166).

NOTES

Only relative targets but no absolute targets can be commanded as long as referencing was not successfully performed.

If the controller is given an incorrect position with POS, the axis can run into a limit switch and will not be able to move away from the switch due to the travel range limits given by the MAX_TRAVEL_RANGE_POS parameter (ID 0x15; ask with TMX? (p. 187)) and the MAX_TRAVEL_RANGE_NEG parameter (ID 0x30; ask with TMN? (p. 186)).

3.6 Using Trigger Input and Output

It is possible to trigger external devices and to program start/stop actions in macros using the digital I/O lines of the E-861. See "I/O Socket" (p. 218) for the lines and pinout. The number of digital I/O lines available on the E-861 can be queried using the TIO? command (p. 186).

You can set the states of the Output 1 to Output 4 lines (TTL, active high) using the DIO command (p. 121), e.g. to trigger other devices. The lines can be set individually or all at once according to a bit pattern. Furthermore, you can program the Output 1 to Output 4 lines using the CTO command (trigger configuration) and the TRO command (trigger enabling/disabling). See "Configuring Trigger Output—Examples" for examples.

The states of the Input 1 to Input 4 lines (TTL, active high) can be queried with the DIO? command (p. 121). These lines can be used to stop macros and to trigger certain actions in macros via the MEX command (p. 149) or the WAC command (p. 189), respectively. See "Working with Controller Macros" (p. 82) for an example.

3.7 Updates

3.7.1 Software Updates

Updated releases of software and manuals are available for download at www.pi.ws. While the manuals are freely accessible, you need a password for the software download. This password is provided on the E-861 CD in the E-861 Releasenews PDF file in the \Manuals directory.

To download the latest software (complete CD mirror) from the PI Website, proceed as follows:

- 1 On the www.pi.ws front page, move the cursor to *Manuals*, *Software*, *ISO Statements* in the *Service* section on the left.
- 2 Select *Software* from the list that pops up.
- 3 On the *PI Download Server* page, enter the Username and the Password which are provided in the E-861 Releasenews xxxxx.pdf on the E-861 CD and click on *Login*
- 4 Click on the *E Piezo Drivers & Nanopositioning controllers* category.
- 5 Click on *E-861*.
- 6 Click on *Software* (if you click on *Documents* you will get the latest manuals).

- 7 Click on the latest CD-Mirror (includes the manual versions that were with the release) or on the latest update zip file.

3.7.2 Updating PISTages2.dat

To install the latest version of *PIStages2.dat* from the PI Website proceed as follows:

1. On the www.pi.ws front page, move the cursor to *Manuals, Software, ISO Statements* in the *Service* section on the left.
2. Select *Software* from the list that pops up.
3. On the *PI Support Site* page, click on the *General Software* category (no login or password is required).
4. Click on *PI Stages*.
5. Click on *pistages2*.
6. In the download window, switch to the `...\PI\GcsTranslator` directory. The location of the PI directory is that specified upon installation, usually in `C:\Documents and Settings\All Users\Application Data` (Windows XP) or `C:\ProgramData` (Windows Vista) (may differ in other-language Windows versions).

Note that in PIMikroMove, you can use the *Version Info* entry in the controller menu or the *Search for controller software* entry in the *Connections* menu to identify the GcsTranslator path.


7. If desired, rename the existing *PIStages2.dat* (if present) so as to preserve a copy for safety reasons.
8. Download the file from the server as *PIStages2.dat*.

3.7.3 Firmware Updates

The current firmware revision of your E-861 is contained in the response to the `*IDN?` command.

Firmware updates can be made by running the TMS320F28XX Updater firmware update program on the host computer. The program is available on the E-861 CD and can be installed with the Setup Wizard or started directly from the `\TMS320F28xx_Updater` directory of the CD. If you want to run the Setup Wizard:

- Insert the E-861 CD in your host PC.

- If the Setup Wizard does not open automatically, start it from the root directory of the CD with the  icon.
- Follow the on-screen instructions, select the "custom" installation and then select the TMS320F28XX Updater.

NOTES

The E-861 whose firmware is to be updated must be directly connected to the host PC (no daisy chain, do not even connect a cable to "RS-232 Out"), and the connection should be made via the RS-232 interface. USB connections are not recommended for firmware updates.

If the controller is in firmware update mode, the DIP switch settings for baud rate and controller address are ignored. The serial connection to the host PC is made with an automatic baud rate setting ("Autobaudrate") in the firmware update program. If the Autobaudrate connection should fail, try again to establish the connection.

When the controller is in firmware update mode, *all* LEDs on the front panel will stay off.

Proceed as follows to update the E-861 firmware:

- 1 Only required if the firmware update introduces new parameters (see the documentation that comes with the update):
In the PITerminal or the *Command Entry* window of PIMikroMove, send SPA? and save the response to a text file for later restoration of the controller parameter values.
- 2 Power down the E-861 and select the firmware update mode using DIP switch 8 on the E-861 front panel:
switch 8 must be set to the ON position
- 3 Start the TMS320F28XX Updater firmware update program.
- 4 Power on the E-861.
- 5 Establish communication between E-861 and host PC in the firmware update program (Autobaudrate connection).
- 6 Perform the update: Select the new bootloader file and the new flash file for the update. Make sure that the correct files are selected in the corresponding fields. Start the update process.
- 7 When the update has finished, close the firmware update program.

- 8 Power down the E-861 and set it back to normal operation using DIP switch 8:
switch 8 must be set to the OFF position
- 9 Power on the E-861. If the firmware update has not introduced new parameters, the E-861 can be started for normal operation with the new firmware. Otherwise proceed with step 10.
- 10 Only required if the firmware update introduces new parameters (see the documentation that comes with the update):
Make sure you have created a parameter backup file (see step 1).
In the PITerminal or the *Command Entry* window of PIMikroMove, send
ZZZ 100 Parameter
to set the new parameters to initial values. Since this command also resets all other parameters, you have to set them back to the values stored in the backup file using SPA (see "Controller Parameters" (p. 35) for details on parameter handling and saving).
Furthermore, check the new parameters with SPA? and set them to plausible values.

4 Controller Parameters

4.1 General Information

In this section you find information about:

- What to consider for first handling of parameter settings
- How to store parameter settings:
 - Storing parameter settings to controller's volatile memory
 - Storing parameter settings to controller's non-volatile memory
 - Storing parameters to volatile and non-volatile memory via commands
- A parameter list with short descriptions of all available parameters, including GEMAC parameters for the sensor's hardware
- A list of Default-Stage-N parameter settings

For information on how to store a set of parameter settings as a user-defined stage database entry on your host PC, see "How to Create a New Stage Type in the PI Stages Database" (p. 98) for detailed instructions. The values of the parameters required for closed-loop operation depend on your mechanics (stage configuration, sensor, load) and have to be adjusted properly before initial operation of a closed-loop system. See "Customizing the System" (p. 89) for detailed information.

For detailed information regarding the parameters for the GEMAC interpolation circuit (IDs 0x7000010 to 0x700001F), see "GEMAC Parameters" (p. 105) and the GEMAC manual IP1000_B_EN.pdf which is provided on the E-861 CD.

Values stored in non-volatile memory are power-on defaults, so that the system can be used in the desired way immediately.

4.2 What to Consider for First Handling of Parameter Settings

To adapt the E-861 to your application, you can modify parameter values. The parameters available depend on the controller firmware. With HPA? (p. 138) you can obtain a list of all available parameters with information about each (e.g. short descriptions). The volatile and non-volatile memory parameter values can be read with the SPA? (p. 178) or SEP? (p. 174) commands, respectively. See "How to Store Parameter Settings" (p. 37) and "Parameters for Customizing" (p. 90) for further information.

CAUTION

Incorrect E-861 parameter values may lead to improper operation or damage of your hardware. Be careful when changing parameters.



Values stored in non-volatile memory are power-on defaults, so that the system can be used in the desired way immediately.

- By default, the controller's non-volatile memory contains parameter settings of Default Stage N.
- With Default-Stage-N's parameter settings, e.g. reference and limit switches are not recognized, and position is commanded in counts.
- When you set up a connection with PIMikroMove you can choose a specific stage database entry.
This database entry contains all required stage-specific parameter settings except the GEMAC parameters of the sensor.
For details about these parameters see "GEMAC Parameters" (p. 105) and the GEMAC manual IP1000_B_EN.pdf which is provided on the E-861 CD.
While choosing the stage type the parameters for that stage type will be loaded automatically from a stage database on the host PC to the controller's volatile memory.
- With stage-specific database entries reference switch, and – for certain stages – limit switches can be recognized, and position is commanded in mm.
- If you want to store parameters that you need permanently for your individual application you can use commands WPA or SEP to store them to non-volatile memory.
See "How to Store Parameter Settings" (p. 37) below for details.
Note that stand-alone operation is only possible if all required parameter settings are stored to non-volatile memory.
- If you want to operate the controller with a custom stage not delivered from PI you can use the Default-Stage-N's stage database entry.
See "Default-Stage-N Parameter Settings" (p. 49) for details.

4.3 How to Store Parameter Settings

You have several possibilities to store parameter settings:

- Store parameter settings to volatile memory in the expanded *Single axis window* of PIMikroMove.
Find details in “Storing Parameter Settings to Volatile Memory Using Expanded Single Axis Window” (p. 37).
- Store parameter settings to non-volatile memory using the main menu of PIMikroMove.
Find details in “Storing Parameter Settings to Non-Volatile Memory Using PIMikroMove Main Window” (p. 38).
- Store parameter settings to volatile or non-volatile memory using commands SPA, SEP, RPA and WPA via a terminal program like PITerminal or via the *Command entry* window of PIMikroMove.
Find details in “Storing Parameters to Volatile and Non-Volatile Memory via Commands” (p. 40).
- Store a set of parameter settings as a user-defined stage database entry in the PI_UserStages2.dat file located on your host PC. It will be loaded automatically to the controller's volatile memory.
See “How to Create a New Stage Type in the PI Stages Database” (p. 98) in Section “Customizing the System” (p. 89) for detailed instructions.

To store parameters according to the presented possibilities requires that:

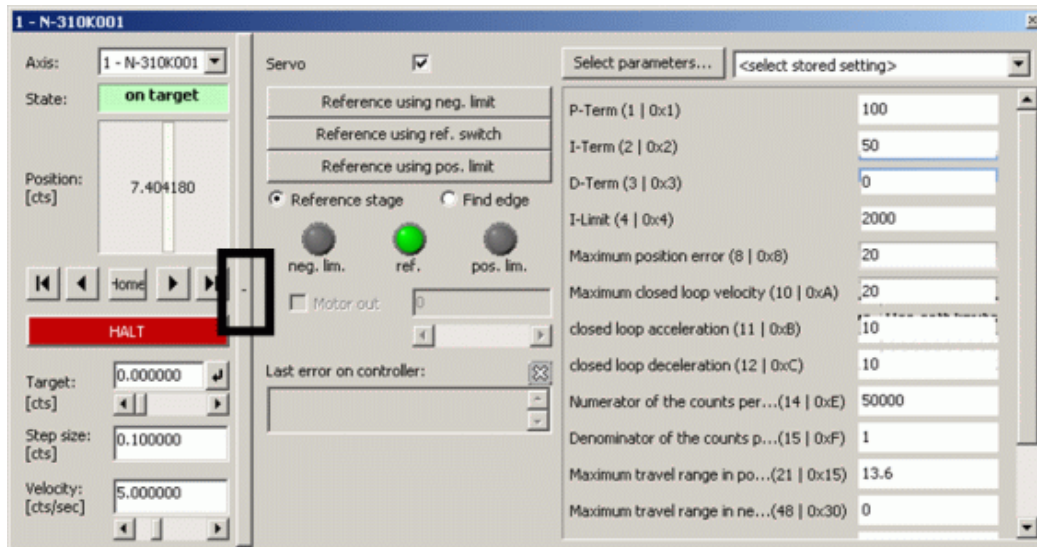
- PIMikroMove or PITerminal must be installed on your host PC, see “Installing the Software on the Host PC” (p. 27) for details.
- Communication between controller and host PC must be established using PIMikroMove (or PITerminal), see “Getting Started” (p. 12) for details.

4.3.1 Storing Parameter Settings to Volatile Memory Using Expanded Single Axis Window

PIMikroMove main window must be open. Proceed as follows to adjust and store parameter settings:

- 1 Open the expanded single axis window by following the *View → Single Axis Window* menu sequence for the connected stage.

- Click on the + at the right side of the single axis window, see figure below.



- In the list at the right side of the expanded single axis window you can insert new settings.
If the parameter you wish to change does not occur in the list click on *Select parameters* to display the parameter in the list.

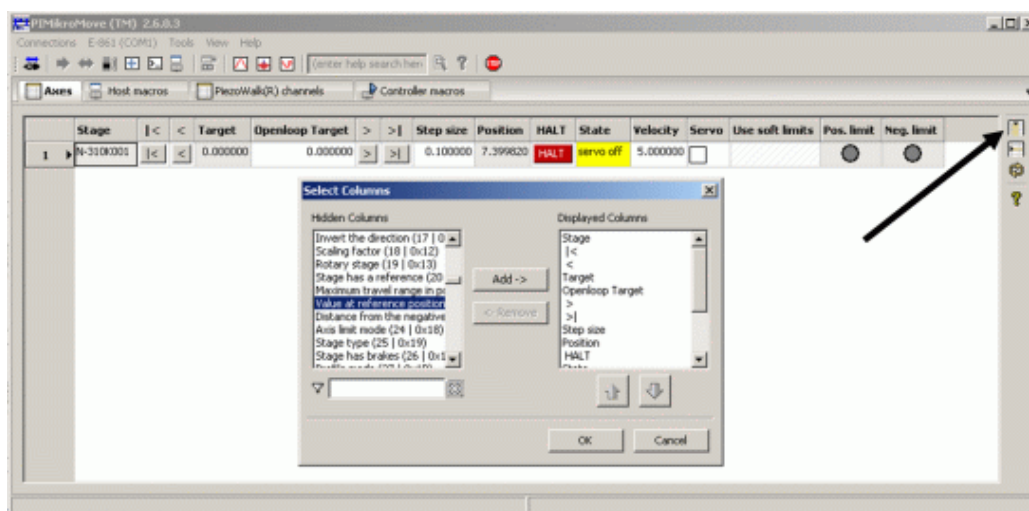
Note that a new parameter setting is only sent to the controller after <ENTER> is pressed while the cursor is in the text entry.

4.3.2 Storing Parameter Settings to Non-Volatile Memory Using PIMikroMove Main Window

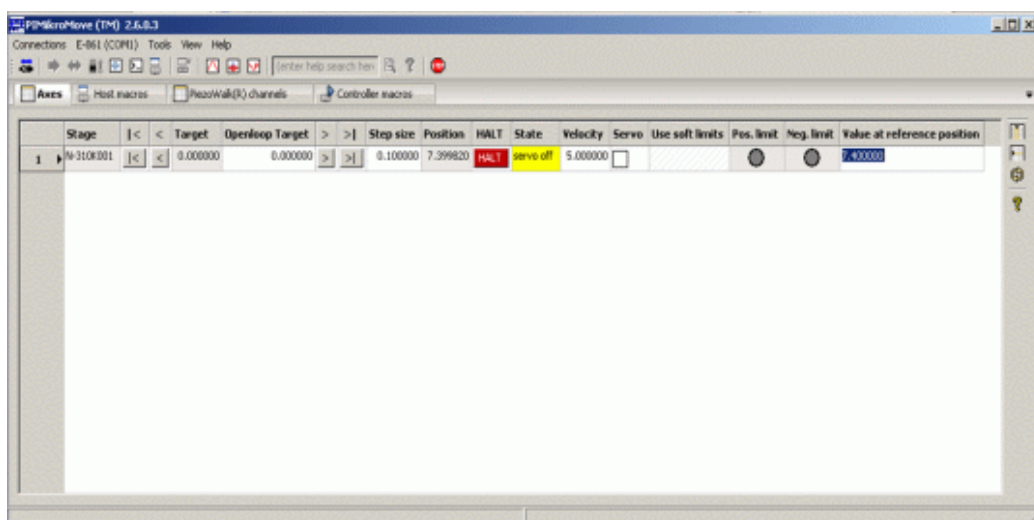
PIMikroMove main window must be open.

The procedure described stores current parameter settings of the controller's volatile memory to non-volatile memory.

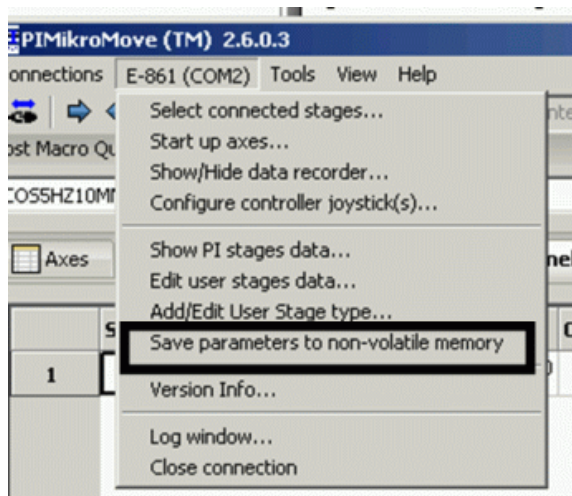
- To select parameters to be adjusted the Axes tab must be displayed.
Press the *Select columns to be displayed* icon in the right top corner of the PIMikroMove main window, see next figure.



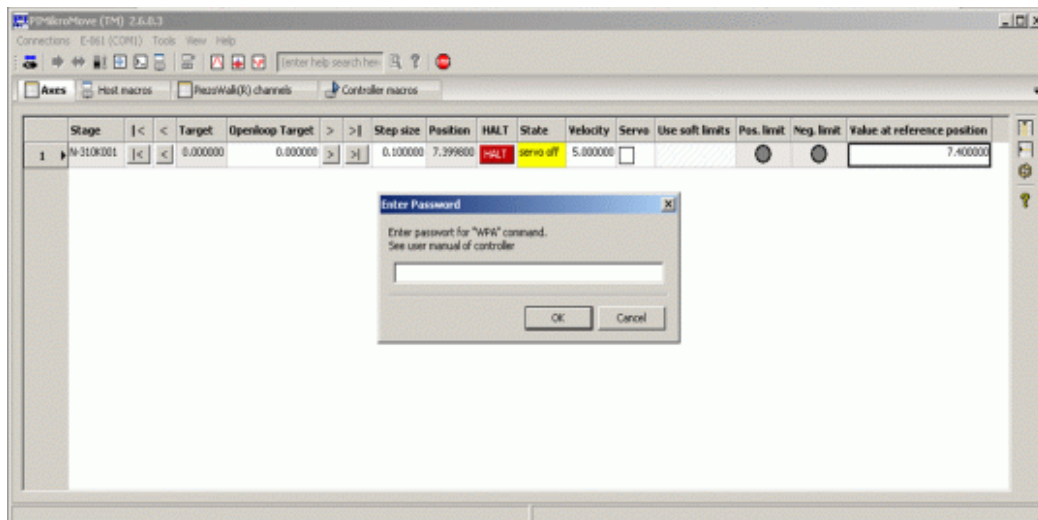
2 Adjust chosen parameter, see next figure.



3 To store adjusted parameter settings follow the *E-861 → Save parameters to non-volatile memory* menu sequence in the PIMicroMove main window, see next figure.



A password is required, see next figure.



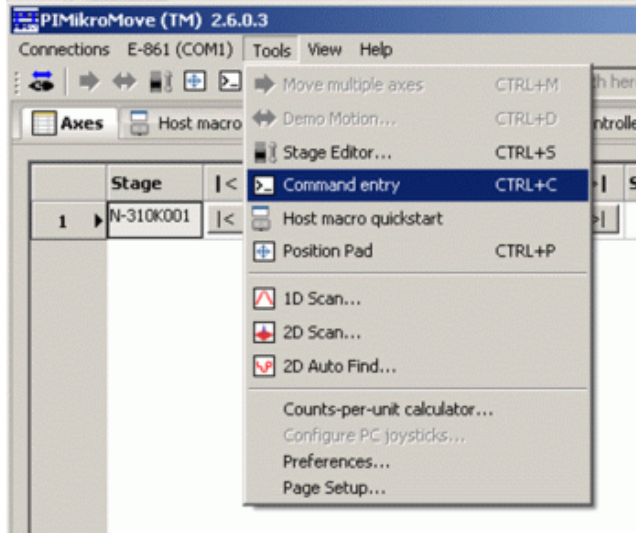
- 4 To store adjusted GEMAC parameter settings to non-volatile memory use password 4711.
For all other parameters use password 100.

Note that the adjusted settings are loaded from non-volatile memory to volatile memory each time you power on or reboot the controller.

4.3.3 Storing Parameters to Volatile and Non-Volatile Memory via Commands

Using the "general" modification commands SPA, RPA, SEP and WPA, parameters can be changed in volatile memory (SPA (p. 175), RPA (p. 171)) or in non-volatile memory (SEP (p. 173), WPA (p. 190)).

- 1 To store parameters using commands follow the *Tools* → *Command entry* menu sequence in the PIMikroMove main window, see next figure.



Example:

To set the slew rate to 100 ms send SPA 1 0x7000002 100.

It is recommended that any modifications be first made with SPA, and when the controller runs well, saved using WPA. In addition to the "general" modification commands, there are commands which change certain specific parameters in volatile memory as e.g. VEL (p. 190) changes 0xA, i.e. the closed-loop velocity (see table below).

4.4 Parameter List



CAUTION

Wrong values of the E-861 parameters may lead to improper operation or damage of your hardware. Be careful when changing parameters.

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
0x1	INT	100	P-Term of PID-parameter set for nanostepping mode	0 to 65535

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
0x2	INT	100	I-Term of PID-parameter set for nanostepping mode	0 to 65535
0x3	INT	100	D-Term of PID-parameter set for nanostepping mode	0 to 65535
0x4	LONG INT	100	I-limit	0 to 2,000,000
0x8	FLOAT	100	Maximum position error (user unit)	Used for stall detection. If the position error (i.e. the absolute value of the difference between current position and commanded position) in closed-loop operation exceeds the given maximum, the controller sets error code -1024 ("Motion error"), the servo will be switched off and the axis stops. Note that with open-loop referencing exceeding of maximum position error is not indicated.
0xA	FLOAT	100	Maximum closed-loop velocity (user unit/s)	Gives the maximum value which can be set with the VEL command (p. 188). On power-on, the closed-loop velocity is set by parameter 0x4B
0xB	FLOAT	100	Current closed-loop acceleration (user unit/s ²), also changed by ACC command (p. 118).	Gives the current closed-loop acceleration limited by parameter 0x4A
0xC	FLOAT	100	Closed-loop deceleration (user unit/s ²), also changed by DEC command (p. 119).	Gives the current closed-loop deceleration limited by parameter 0x4B
0xE	INT	100	Numerator of the counts-per-physical-unit factor	1 to 1,000,000 for each parameter.

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
0xF	INT	100	Denominator of the counts-per-physical-unit factor	The counts-per-physical-unit factor determines the "user" unit for closed-loop motion commands. When you change this factor, all other parameters whose unit is based on the "user" unit are adapted automatically, e.g. closed-loop velocity and parameters regarding the travel range.
0x14	INT	100	Stage has a reference	1 = the stage has a reference, else 0
0x15	FLOAT	100	MAX_TRAVEL_RANGE_POS The maximum travel in positive direction (user unit)	"Soft limit", based on the home (zero) position. If the soft limit is smaller than the position value for the positive limit switch (which is given by the sum of the parameters 0x16 and 0x2F), the positive limit switch cannot be used for referencing. Smallest possible value is 0.
0x16	FLOAT	100	VALUE_AT_REF_POS The position value at the reference position (user unit)	The position value which is to be set when the mechanics performs a reference move to the reference switch.
0x17	FLOAT	100	DISTANCE_REF_TO_N_LIM The distance between reference switch and negative limit switch (user unit)	Represents the physical distance between the reference switch and the negative limit switch integrated in the mechanics. When the mechanics performs a reference move to the negative limit switch, the position is set to the difference of VALUE_AT_REF_POS and DISTANCE_REF_TO_N_LIM.
0x18	INT	100	Axis limit mode	0 = positive limit switch active high (pos-HI), negative limit

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
				switch active high (neg-HI) 1 = positive limit switch active low (pos-LO), neg-HI 2 = pos-HI, neg-LO 3 = pos-LO, neg-LO
0x2F		100	DISTANCE_REF_TO_P_LIM The distance between reference switch and positive limit switch (user unit)	Represents the physical distance between the reference switch and the positive limit switch integrated in the mechanics. When the mechanics performs a reference move to the positive limit switch, the position is set to the sum of VALUE_AT_REF_POS and DISTANCE_REF_TO_P_LIM.
0x30	FLOAT	100	MAX_TRAVEL_RANGE_NEG The maximum travel in negative direction (user unit)	"Soft limit", based on the home (zero) position. If the soft limit is smaller than the absolute value of the position set for the negative limit switch (i.e. the difference of the parameters 0x16 and 0x17), the negative limit switch cannot be used for referencing. Smallest possible value is 0.
0x31	INT	100	Invert the reference	1 = invert the reference, else 0
0x32	INT	100	Stage has limit switches; enables / disables the stopping of the motion at the limit switches	0 = Stage has limit switches 1 = Stage has no limit switches
0x36	INT	100	Settle window (counts)	In closed-loop operation, the on-target status is true when the current position is inside the settle window and stays there for at least the settle time (parameter ID 0x3F). The settle window is centered around the target position. The minimum value for stable positioning is 2.
0x3C	STRING	100	Stage name	Default is "DEFAULT_STAGE-N"
0x3F	FLOAT	100	Settle time (s)	0 to 1.000 s; see Settle window
0x47	INT	100	Default direction for	0 = detect automatically,

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
			reference	1 = start in negative direction, 2 = start in positive direction
0x49	FLOAT	100	Current closed-loop velocity (user unit/s) also changed by VEL command (p. 188)	Gives the current closed-loop velocity limited by parameter 0xA
0x4A	FLOAT	100	Maximum closed-loop acceleration (user unit/s ²)	Gives the maximum value which can be set with the ACC command (p. 118) (for parameter 0xB)
0x4B	FLOAT	100	Maximum closed-loop deceleration (user unit/s ²)	Gives the maximum value which can be set with the DEC command (p. 119) (for parameter 0xC)
0x50	FLOAT	100	Closed-loop referencing velocity (user units/s)	Is limited by Maximum closed-loop velocity parameter (ID 0xA)
0x5A	INT	100	Numerator of servo loop input factor	1 to 1,000,000 for each parameter The servo loop input factor decouples servo loop parameters from the encoder resolution. Not to be changed by the customer. Note that the servo loop input factor is independent from 0xE and 0xF, i.e. the counts-per-physical-unit factor. The counts-per-physical-unit factor has no influence on control loop stability, but is used for input and output scaling of position values.
0x5B	INT	100	Denominator of servo loop input factor	
0x94	FLOAT	100	Notch filter frequency 1 (Hz)	40 to 20000 The corresponding frequency component in the control value is reduced to compensate for unwanted resonances in the mechanics. Only active in closed-loop operation. Should normally not be changed (try to change only with very high loads).
0x95	FLOAT	100	Notch filter edge	0.1 to 10 Gives the slope of the filter

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
				edge. Do not change.
0xAC	FLOAT	100	Low-pass filter frequency (Hz)	40 to 20000 Gives the cut-off frequency of a low-pass filter which is only active in closed-loop operation and with analog mode motion
0x401	INT	100	P term of PID-parameter set for analog mode	0 to 65535
0x402	INT	100	I term of PID-parameter set for analog mode	0 to 65535
0x403	INT	100	D term of PID-parameter set for analog mode	0 to 65535
0x7000000	INT	100	Travel range minimum (user unit)	By default set to a very large value which should not be changed. Can be used as travel range limit for open-loop motion with OSM (p. 163), OAD (p. 155), OMA (p. 158), OMR (p. 161): if the current position reaches this value, the motion is stopped. In this case, enlarge the limit.
0x7000001	INT	100	Travel range maximum (user unit)	By default set to a very large value which should not be changed. Can be used as travel range limit for open-loop motion with OSM (p. 163), OAD (p. 155), OMA (p. 158), OMR (p. 161): if the current position reaches this value, the motion is stopped. In this case, enlarge the limit.
0x7000002	INT	100	Slewwrate (ms)	1 to 1000 ms This value affects the time which is required for the "preparing for motion" and "relaxing" changes of the motion state. Depending on the current motion state, a change of state can take up to four times the slewwrate value. See "Modes of Operation" (p. 54) for details.

Parameter ID (hexadecimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
0x7000003	FLOAT	100	Bending voltage, also changed by SSA command (p. 180)	0 to 55 V, gives the step size for open-loop nanostepping motion
0x7000004	INT	100	Time to close servo (ms)	1 to 1000 ms Gives the time interval between obtaining trajectory voltage and closing of servo-loop
0x7000201	FLOAT	100	Current open-loop velocity (step cycles/s), also changed by OVL command (p. 165)	Gives the current open-loop velocity, limited by parameter 0x7000204. On power-on, the current open-loop velocity is set by parameter 0x7000201.
0x7000202	FLOAT	100	Current open-loop acceleration (step cycles/s ²), also changed by OAC command (p. 154)	Gives the current open-loop acceleration, limited by parameter 0x7000205.
0x7000203	FLOAT	100	Current open-loop deceleration (step cycles/s ²), also changed by ODC command (p. 157)	Gives the current open-loop deceleration, limited by parameter 0x7000206.
0x7000204	FLOAT	100	Maximum open-loop velocity (step cycles/s)	Gives the maximum value which can be set with the OVL command (p. 165) (for parameter 0x7000201).
0x7000205	FLOAT	100	Maximum open-loop acceleration (step cycles/s ²)	Gives the maximum value which can be set for parameter 0x7000202
0x7000206	FLOAT	100	Maximum open-loop deceleration (step cycles/s ²)	Gives the maximum value which can be set for parameter 0x7000203
0x7000207	INT	100	Open-loop referencing velocity (step cycles/s)	Is limited by Maximum open-loop velocity parameter (ID 0x7000204)
0x7001A00	INT	100	PiezoWalk Driving mode	Determines how closed-loop motion is performed: 0 = nanostepping mode only 1 = alternating sequence of analog mode and nanostepping mode
0x7000601	CHAR		Axis unit	This parameter has to be set consistent with the counts-per-physical-units factor given by

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
				parameters 0xE and 0xF
0x7000010		4711	GEMAC parameter 0 (Write register CFG0 on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000011		4711	GEMAC parameter 1 (Write register CFG1 on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000012		4711	GEMAC parameter 2 (Write register CFG2 on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000013		4711	GEMAC parameter 3 (Write register ERRMASK on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000014		4711	GEMAC parameter 4 (Write register PHASE on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000015		-	GEMAC parameter 5 (reserved)	Read only. Not included in SEP? response
0x7000016		-	GEMAC parameter 6 (reserved)	Read only. Not included in SEP? response
0x7000017		4711	GEMAC parameter 7 (Write register SGAIN on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000018		4711	GEMAC parameter 8 (Write register SOFF on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x7000019		4711	GEMAC parameter 9 (Write register CGAIN on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x700001A		4711	GEMAC parameter 10 (Write register COFF on the GEMAC interpolation circuit)	Can be set with SPA and saved with WPA. Not available for SEP and SEP?
0x700001B		4711	GEMAC parameter 11	Can be set with SPA and

Parameter ID (hexa-decimal)	Data Type	Password for Writing to Non-Volatile Memory	Parameter Description	Possible Values/Notes
			(Write register SYNC on the GEMAC interpolation circuit)	saved with WPA. Not available for SEP and SEP?
0x700001C		-	GEMAC parameter 12 (internal use)	Read only. Not included in SEP? response
0x700001D		-	GEMAC parameter 13 (internal use)	Read only. Not included in SEP? response
0x700001E		-	GEMAC parameter 14 (internal use)	Read only. Not included in SEP? response
0x700001F		-	GEMAC parameter 15 (internal use)	Read only. Not included in SEP? response

4.5 Default-Stage-N Parameter Settings

If you purchased an E-861 controller without a NEXACT® stage parameter settings as listed below are stored on the controller's non-volatile memory.

If you operate a NEXACT® stage with an E-861 NEXACT® controller, you can send the following query commands via a terminal program like PITerminal, or via the command entry of PIMikroMove:

- HPA? to get a list of all available parameters with short descriptions
- SPA? to get all parameters with their present values as they are set in the controller's volatile memory

Note that with Default-Stage-N parameter settings, e.g. reference and limit switches are not recognized (0x32 for limit switches is set to 1), and position is commanded in counts.

The response to SPA? delivers the parameter settings:

```
==== new connection: E-861 on RS-232: COM1, 9600 baud ====
>>*IDN?
<<(c)2010 Physik Instrumente(PI) Karlsruhe,E-861 Version 7.2.0
>>spa?
<<1    0x1      =    100
<<1    0x2      =    50
<<1    0x3      =    0
<<1    0x4      =   2000
```



```

<<1 0x8      = 1000000.0
<<1 0xA      = 1000000.0
<<1 0xB      = 500000.0
<<1 0xC      = 500000.0
<<1 0xE      = 1
<<1 0xF      = 1
<<1 0x14     = 0
<<1 0x15     = 2147483647.0
<<1 0x16     = 0.0
<<1 0x17     = 2147483647.0
<<1 0x18     = 0
<<1 0x2F     = 2147483647.0
<<1 0x30     = -2147483647.0
<<1 0x31     = 0
<<1 0x32     = 1
<<1 0x36     = 10
<<1 0x3C     = DEFAULT_STAGE-N
<<1 0x3F     = 0.010000
<<1 0x47     = 0
<<1 0x49     = 250000.0
<<1 0x4A     = 10000000.0
<<1 0x4B     = 10000000.0
<<1 0x50     = 100000.0
<<1 0x5A     = 50000
<<1 0x5B     = 1
<<1 0x94     = 10000.000
<<1 0x95     = 0.800
<<1 0xAC     = 200.000
<<1 0x401    = 100
<<1 0x402    = 100
<<1 0x403    = 0
<<1 0x7000000 = -2147483647.0
<<1 0x7000001 = 2147483647.0
<<1 0x7000002 = 10
<<1 0x7000003 = 55.0000
<<1 0x7000004 = 10
<<1 0x7000201 = 200
<<1 0x7000202 = 2000
<<1 0x7000203 = 2000
<<1 0x7000204 = 1500
<<1 0x7000205 = 2000
<<1 0x7000206 = 2000
<<1 0x7000207 = 100
<<1 0x7001A00 = 0
<<1 0x7000601 = counts
<<1 0x7000010 = 252
<<1 0x7000011 = 10
<<1 0x7000012 = 60
<<1 0x7000013 = 0
<<1 0x7000014 = 15
<<1 0x7000015 = 0
<<1 0x7000016 = 0
<<1 0x7000017 = 128
<<1 0x7000018 = 0
<<1 0x7000019 = 128
<<1 0x700001A = 0
<<1 0x700001B = 0
<<1 0x700001C = 255
<<1 0x700001D = 0
<<1 0x700001E = 0
<<1 0x700001F = 70

```

5 System Description

5.1 Basic Elements

For successful operation of the E-861, you should familiarize yourself with the following features of the device.

Logical Axes:

The E-861 controls one logical axis of a mechanics. See "Accessible Items and Their Identifiers" (p. 53) for details.

Input and Output Signals:

Input and output signals can be used for triggering purposes, and the input signals of a joystick can furthermore be used for velocity control of the E-861. See "Accessible Items and Their Identifiers" (p. 53) for details.

Communication Interfaces:

The E-861 can be controlled from a host computer (not included) with ASCII commands sent via:

- RS-232 serial connection
- USB interface: The USB drivers will make the USB interface appear to all software on the host PC as a new COM port. That port will be present only when the controller is connected via USB and powered on.



CAUTION

Never connect the RS-232-IN and USB connectors of the same controller to a PC at the same time as this can cause damage to the controller.

Up to 16 E-861 controllers can be controlled from a single host computer interface via a daisy chain.

See "Connecting Controller or Daisy-Chain Network to Host PC" (p. 27) for more information.

Controller Firmware:

The firmware comprises the ASCII command set and the controller parameters. For version information and updates see "Firmware Update".

- ASCII Commands:

The E-861 understands the PI General Command Set (GCS; version 2.0).

The PI General Command Set (GCS) is supported by a wide range of PI systems. This command set is well-suited for positioning tasks with one or more axes. The command set itself is independent of the specific hardware (controller or attached stages).

Commands are used, for example, to set operating modes, to initiate motion of the mechanics and to query system and motion values. See "GCS Commands" (p. 107) for more information.

■ Controller Parameters:

The hardware basics of the motion system (controller and connected mechanics) are mirrored in controller parameters. Some of the parameters are protected so that their factory settings cannot be changed, other parameters can be modified by the user to adapt the system to the individual application. See "Controller Parameters" (p. 35) and "Customizing the System" (p. 89) for more information.

■ Special Features:

Data recorder: The E-861 comprises a real-time data recorder. It is able to record several signals (e.g. current position, analog input) from different data sources (e.g. logical axes or input channels). See "Data Recording" (p. 88) for more information.

Macros: The E-861 can store macros. The macro feature allows defining command sequences and storing them permanently in non-volatile memory in the device. It is possible to define a macro that will be executed automatically every time the E-861 is started, facilitating stand-alone operation without a host computer. See "Working with Controller Macros" (p. 82) for more information.

■ Control algorithm for Closed-Loop Operation:

For better position accuracy and performance, the E-861 can be operated in closed-loop mode. A proportional-integral-differential (P-I-D) servo-control algorithm (with sensor feedback) will then apply corrections to the internal control value. See "Tuning PID Control Parameters" (p. 95) for more information.

Software on Host PC

Usually, a host computer is used to operate or at least configure the E-861. Therefore an ample array of software tools for installation on the host computer comes with the E-861. For a complete list of all software on the E-861 CD, see "Software Description" (p. 10).

5.2 Accessible Items and Their Identifiers

The identifiers listed below are used to address the appropriate items with the commands of the PI General Command Set (GCS) which is supported by the firmware of the E-861.

The identifiers of the following items are factory defaults and cannot be changed by the user:

- Logical axis/PiezoWalk channel: one axis/PiezoWalk channel, the identifier is 1.
In the E-861 firmware, motion for logical axes (i.e. for the directions of motion of a stage) is commanded with the closed-loop move commands MOV (p. 151) and MVR (p. 153) and with the open-loop move commands OMA (p. 158) and OMR (p. 161).
Motion for PiezoWalk channels (i.e. for single NEXACT® linear drives) is commanded using the open-loop move commands OAD (p. 155) and OSM (p. 163).
Since the E-861 is a single-axis / single-channel device, the terms "axis" and "PiezoWalk channel" can be used synonymously.
- Analog input channels: six channels, the identifiers are 1 to 6.
"Genuine" analog input lines, with the identifiers 1 to 4, are Input 1 to Input 4 on the I/O socket (p. 218). Their number is reported by the TAC? command (p. 185), and their values can be queried with the TAV? command (p. 185). Note that these lines can also be used for digital input (see below).
Further analog input lines are located on the Joystick socket (p. 220): channel 5 is the input line for the joystick axis and 6 the input line for the joystick button. They are not reported by TAC? and TAV? commands. See also the Joystick information below.
The values of all six channels can be recorded using the record option 81 of the DRC command (p. 122).
- Digital output lines: four lines, the identifiers are 1 to 4.
1 to 4 identify the Output 1 to Output 4 digital output lines on the I/O socket (p. 218).
See "Using Trigger Input and Output" (p. 31) for more information.
- Digital input lines: four lines, the identifiers are 1 to 4.
1 to 4 identify the Input 1 to Input 4 digital input lines on the I/O socket (p. 218) which can also be used for analog input (see above).
See "Using Trigger Input and Output" (p. 31) for more information.
- Joystick: one joystick device, identifier is 1 with all joystick-related commands. Note that the second joystick device shown in some responses is an analog input which is currently deactivated and provided for future applications.

The E-861 supports one axis and one button of the joystick. The identifier of the joystick axis is 1 with joystick-related commands (JAS? (p. 138), JAX (p. 139), JAX? (p. 140), JDT (p. 141), JLT (p. 142), JLT? (p. 143)) and 5 with the DRC command, record option 81. The identifier of the joystick button is 1 with the joystick-related JBS? command (p. 140) and 6 with the DRC command, record option 81. See "Joystick Control" (p. 79) and "Joystick Socket" (p. 220) for more information.

- Data recorder tables (memory tables for recorded data): 2 tables with 1024 points per table, the identifiers are 1 and 2. See "Data Recording" (p. 88) for more information.

Each E-861 must have a unique controller address. The controller address can be changed by the user if, for example, a daisy chain network is to be set up:

- Controller address: the E-861 device address in the range of 1 to 16 and, in a daisy-chain, one controller must have address 1. The address can be set with the DIP switches on the front panel, see "DIP Switch Settings" and "Target and Sender Address" (p. 110) for details.

5.3 Modes of Operation

In this section you find information about the following items:

- Servo modes
- Motion modes, including:
 - A short description of the nanostepping mode working principle
 - A short description of the analog mode working principle
 - An assignment of move commands to motion and servo modes
- Changing motion and servo mode including states and transitions implemented in the controller's firmware
- PiezoWalk Driving mode parameter, i.e. automatic alternating between nanostepping and analog motion modes, including:
 - A short description of the PiezoWalk Driving mode parameter
 - Advantages of alternating motion modes
 - What to consider if using automatic alternating of the two motion

modes

Motion sequence

Sequence of transitions and states

- Application notes

5.3.1 Servo Modes

The E-861 provides the following servo modes:

- Open-loop operation (also referred to as "servo-off state" in this document): sensor feedback is not used
- Closed-loop operation (also referred to as "servo-on state" in this document): sensor feedback participates in the internal control value generation.
A proportional-integral-differential (P-I-D) servo-controller is used to generate corrections to the internal control value. In addition, velocity, acceleration, deceleration as well as settle time and settle window values are accessible as parameters. See "Parameters for Customizing" (p. 90) and "Tuning PID Control Parameters" (p. 95) for more information.

The servo mode can be selected with the SVO command (p. 183). Open-loop operation is active after power-on. Using a start-up macro, you can set up the device to start with closed-loop operation (see "Working with Controller Macros" (p. 82) for more information).

You can query the current servo mode using the SVO? command (p. 185) or with the #4 (p. 114) and SRG? commands (p. 178) which have a bit-coded response.

For additional information see also "Control Value Generation" (p. 68), "Control Algorithm" (p. 76) and "PiezoWalk Driving Mode" (p. 63).



CAUTION

If no sensor is present in your system:

- Do not switch servo on (SVO command)
 - Do not send commands for closed-loop motion, like MOV or MVR
 - Do not send the open-loop commands OMA and OMR, since they use a sensor, too
-

Otherwise the connected mechanics can run into the hard stop at full speed, which may cause damage to your hardware setup.

5.3.2 Motion Modes

With the NEXACT® design two basic motion modes are realized based on the design of a NEXACT® piezo drive module:

A piezo drive module consists of four NEXACT® piezo actuators. The individual actuators themselves each consist of two segments (Figure 4) of piezo bender elements.

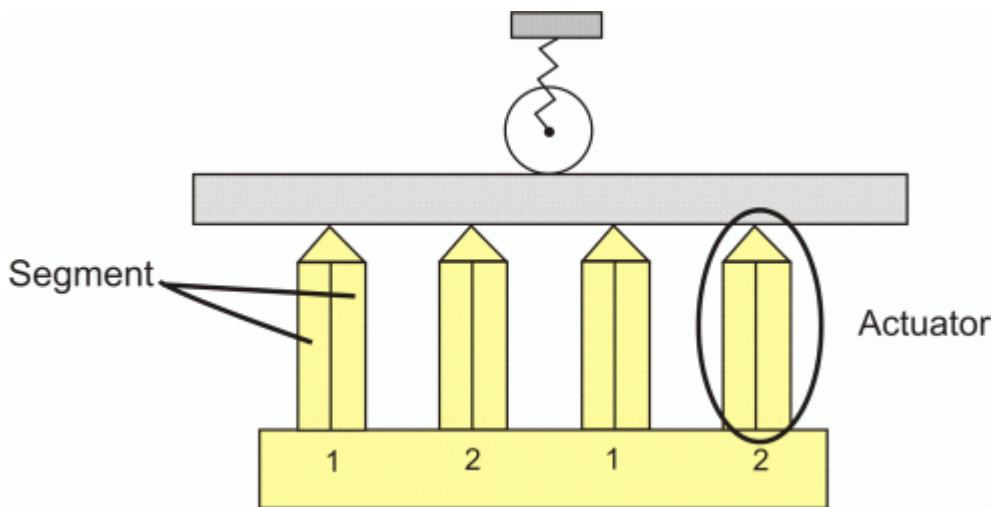


Figure 4: Design of NEXACT® piezo drive module. The four NEXACT® piezo actuators each consist of two segments. The numbers 1, 2 designate the actuator pairs which are controlled in an identical way

The actuators of a piezo drive module are all cyclically controlled in pairs (= actuator pairs). When a drive contains several piezo drive modules, corresponding actuator pairs are controlled together. Every NEXACT® drive therefore has to be controlled by means of four different signals for the segments (U1 to U4). The voltage range for the bender elements is -10 to +45 V.

The feed is achieved by coordinated control of the segments. The actuator pairs have different displacements. This causes the piezo drive module to execute a stepping motion on the runner (see Nanostepping mode).

The two motion modes of the NEXACT® linear drives are implemented in the E-861 firmware.

Nanostepping mode

Characteristics:

- Stepping motion over long distances
- High velocity over longer travel ranges, limited only by the length of the runner
- Motion consists of multiple steps of about 10 µm in length at minimum (without load; 5 µm with 10 N load), values can vary depending on the stage type.

Control:

In nanostepping mode the segments of both pairs of legs are controlled with a phase shift. Decisive for the feed of the runner are the resulting voltages below:

Actuator pair 1 (U₁, U₂
in Figure 5)

Clamping voltage

$$U_{clamping} = \frac{U_1 + U_2}{2}$$

Feed voltage

$$U_{feed} = U_1 - U_2$$

Actuator pair 2 (U₃, U₄
in Figure 5)

$$U_{clamping} = \frac{U_3 + U_4}{2}$$

$$U_{feed} = U_3 - U_4$$

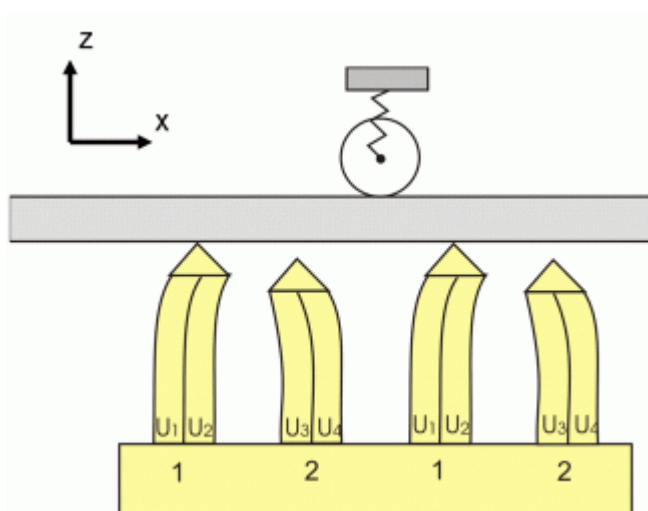


Figure 5: The runner moves in the X-direction. The module is preloaded against the runner in Z-direction.

The motion is realized by coordinated control of the feed and clamping voltages for the piezo stacks in the NEXACT® drive, and can cover the whole travel range of the mechanics.

Analog mode

Characteristics:

- High-dynamics motion, limited by the step size in analog mode (a few μm)
- Positioning accurate to one picometer (open-loop)

Control:

All actuators are controlled in phase. The clamping voltage in analog mode is 17.5 V, and hence the mean value of the possible piezo voltages of both segments. The maximum travel range is thus available for the deflection (see Figure 6).

NOTES

The actual step size can vary with the applied load.

The step size can differ for both directions of motion, depending on the direction of force applied by the load: steps in the direction of the load may be larger than the average step size, steps against the load may be smaller.

The following motion commands are available:

- Open-loop operation (servo off), nanostepping mode:
 - OSM (p. 163)
 - OMA (p. 158)
 - OMR (p. 161)

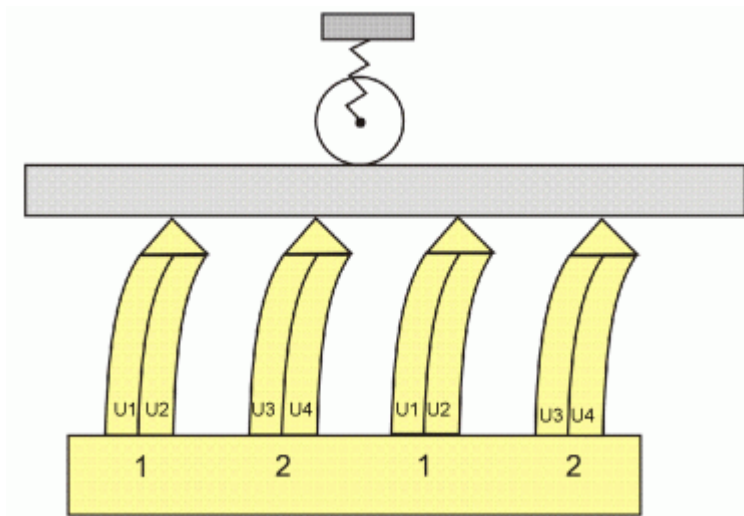


Figure 6: Analog mode: All NEXACT® piezo actuators are in contact with the runner. The actuator pairs 1 and 2 are controlled in an identical way (segment voltages $U1 = U3$, $U2 = U4$)

NOTE

With the OSM command steps are commanded using floating point numbers, i.e. motion is not limited to complete steps only.

- Open-loop operation (servo off), analog mode:
OAD (p. 155)
- Closed-loop operation (servo on):
MOV (p. 151)
MVR (p. 153)

5.3.3 Changing Motion and Servo Mode

The working principle of a NEXACT® linear drive requires defined transitions between the individual motion and servo modes. For that purpose, the following transitions and states are provided (the numbers given below identify the transitions and states in the responses to the #4 command (p. 114) and the SRG? command (p. 178)):

- *Relaxing* transitions (1) in which the NEXACT® linear drive is brought to a full-holding-force, zero-drive-voltage *Relaxed* state (3). *Relaxing* transitions are performed for the following actions:
 - Switching the servo mode off with
SVO <AxisID> 0

to change from closed-loop motion (MOV (p. 151), MVR (p. 153)) to open-loop nanostepping motion (OSM (p. 163), OMA (p. 158) or OMR (p. 161)) or to open-loop analog motion (OAD (p. 155)) includes an automatic *Relaxing* procedure.

- Starting *Relaxing* manually with
RNP <PiezoWalkChanID> 0
Sending an RNP command (p. 168) is required in open-loop operation each time you want to change from nanostepping motion (OSM, OMA or OMR) to analog motion (OAD) or vice versa.
It is also required if you want to change from analog motion to closed-loop operation.

- Transitions which prepare the NEXACT® linear drive automatically for the desired motion mode by adjusting the drive voltages (transport and clamping voltages) accordingly.
The duration of *Relaxing* transition (1), *Go to analog* transition (2) and *Go to motion* transition (5) is determined by the slew rate (parameter ID 0x7000002).

Note that for all figures below, the following is valid:

The numbers in brackets give the transition state (bits 8 to 11 in the response SRG? <AxisID>) and the servo mode (response to SVO? <AxisID>).

#7 command (p. 116) queries if the controller is ready to perform a new command. The response ° means that the controller is busy.

- *Transitions for open-loop analog motion:*

Go to analog transition (2), is done by the first OAD sent for a NEXACT® linear drive which is in the *Relaxed* state.

Go to analog transition (2) brings the drive in the *Analog* state (0).

Once the drive is in the *Analog* state, each subsequent OAD command will be executed immediately without any *Go to analog* transition.

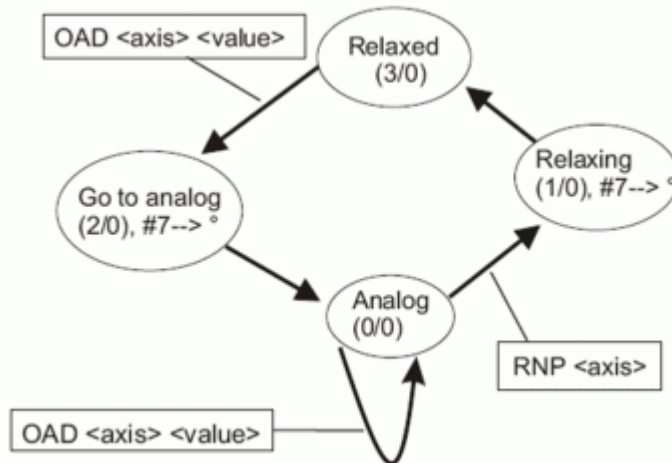


Figure 7: Changing states with a first sent OAD (open-loop analog motion)

- *Transitions for open-loop nanostepping motion:*

Go to motion transition (5) in open-loop operation, is done by the first OSM, OMA or OMR sent for a NEXACT® linear drive which is in the *Relaxed* state.

Go to motion transition (5) brings the drive in the *In Motion state* (4).

Once the drive is in the *In Motion* state, each subsequent OSM, OMA or OMR command will be executed immediately without any *Go to motion* transition.

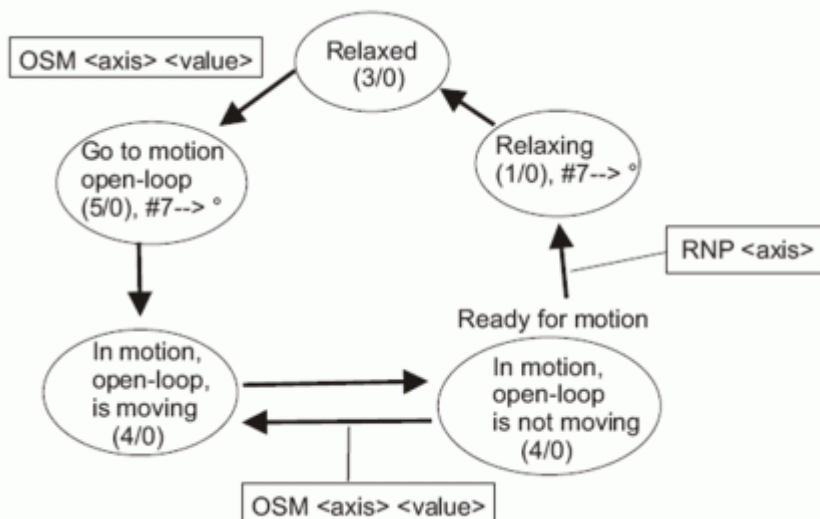


Figure 8: Changing states with a first sent OSM (open-loop nanostepping motion). Analog transitions are valid for first sent OMA or OMR commands.

- *Transitions for closed-loop motion*

Go to motion transition (5) in closed-loop operation, is done when

SVO <AxisID> 1

is sent to switch servo on for a NEXACT® linear drive which is in the *Relaxed* state.

Go to motion transition (5) brings the drive in the *In Motion* state (4).

Note that after switching servo on the controller can be busy for approximately 100 ms, depending on slewrate setting.

Once the drive is in the *In Motion* state in closed-loop operation, each subsequent closed-loop move command (e.g. MOV or MVR) will be executed immediately without any *Go to motion* transition.

Note that if the drive is in open-loop operation and in the *In Motion* state (i.e. open-loop nanostepping motion was done with OSM, OMA or OMR), switching servo on will cause no *Go to motion* transition, and the drive is immediately ready for closed-loop motion.

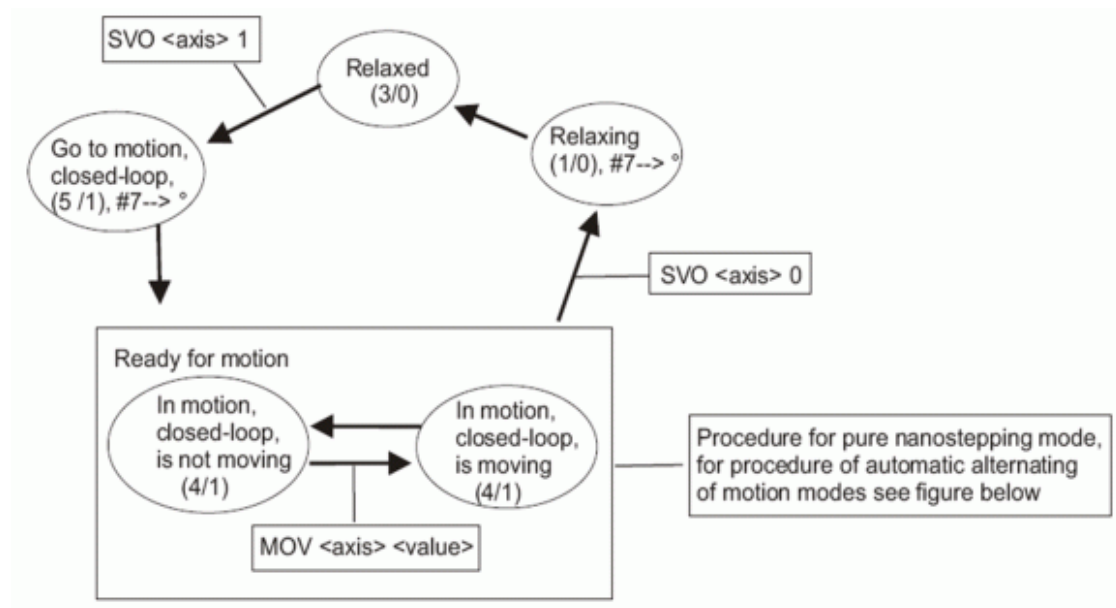


Figure 9: Changing states with first sent SVO command for subsequent closed-loop motion

5.3.4 PiezoWalk Driving Mode

Closed-loop motion can be realized either as nanostepping motion or as a mix of analog mode motion and nanostepping motion. The decision for one of the options depends on your application.

See below for the decision criteria and further details.

Switching between the two options is done via the PiezoWalk Driving Mode parameter (ID 0x7001A00). Note that only if servo is on you can activate automatical alternating of motion modes by setting the PiezoWalk Driving Mode parameter to 1 with the SPA command (p. 175).

Thus the following two options exist with closed-loop operation:

A) With 0x7001A00 set to 0:

- only nanostepping mode is used
- PID parameters for nanostepping mode are:
 - 0x1 for P-term
 - 0x2 for I-term
 - 0x3 for D-term

B) With 0x7001A00 set to 1:

- An alternating sequence of analog mode and nanostepping mode is used
- Two PID parameter sets:
 - PID set for nanostepping mode, as listed above
 - PID set for analog mode, as listed below:
 - 0x401 for P-term
 - 0x402 for I-term
 - 0x403 for D-term

Advantages of Alternating Motion Modes

- Increased stiffness when axis is on target (compared to use of nanostepping mode)
- Provided that system features appropriate mechanics, increased accuracy can be obtained due to two PID parameter sets

- The piezo voltages can be reduced (compared to motion in pure nanostepping mode), increasing the actuators' lifetime

What You Have to Consider When Closed-Loop Motion is Realized With Alternating Motion Modes

- Depending on load and motion direction, settling can require repeated change of motion mode. This may cause a repeated opening and closing of the servo-loop.
- Positioning may take longer than if you use only nanostepping mode.
- For accurate positioning, sensors of the system must have a minimum resolution of 20 nm.

Motion Sequence

How to perform closed-loop motion as a mix of analog and nanostepping mode:

- 1 Make sure that servo is on
You can check the servo state using the SVO? command (p. 185) (response must be 1=1).
To activate servo send:
SVO 1 1
- 2 Make sure that parameter 0x7001A00 is set to 1.
You can check the parameter value using the SPA? command (p. 178).
Send SPA? 1 0x7001A00
To set the parameter send:
SPA 1 0x7001A00 1
- 3 Command motion with MOV or MVR.

Motion starts and ends in analog mode where the target position is maintained with maximum stiffness, since both piezo stack pairs are in contact with the runner of the NEXACT® linear drive. See Figure 10 for detailed motion sequence.

With each change of motion mode (from analog mode to nanostepping mode and vice versa) a *Relaxing* procedure is performed automatically, see "Changing Motion and Servo Mode" (p. 59), and servo is switched off and on automatically.

The criteria for the changes between the motion modes are given by the E-861 firmware and cannot be changed.

Any changes of piezo voltage -as they occur with *Relaxing* procedures - can induce undesired motion. Therefore checks as described in Figure 10 are necessary.

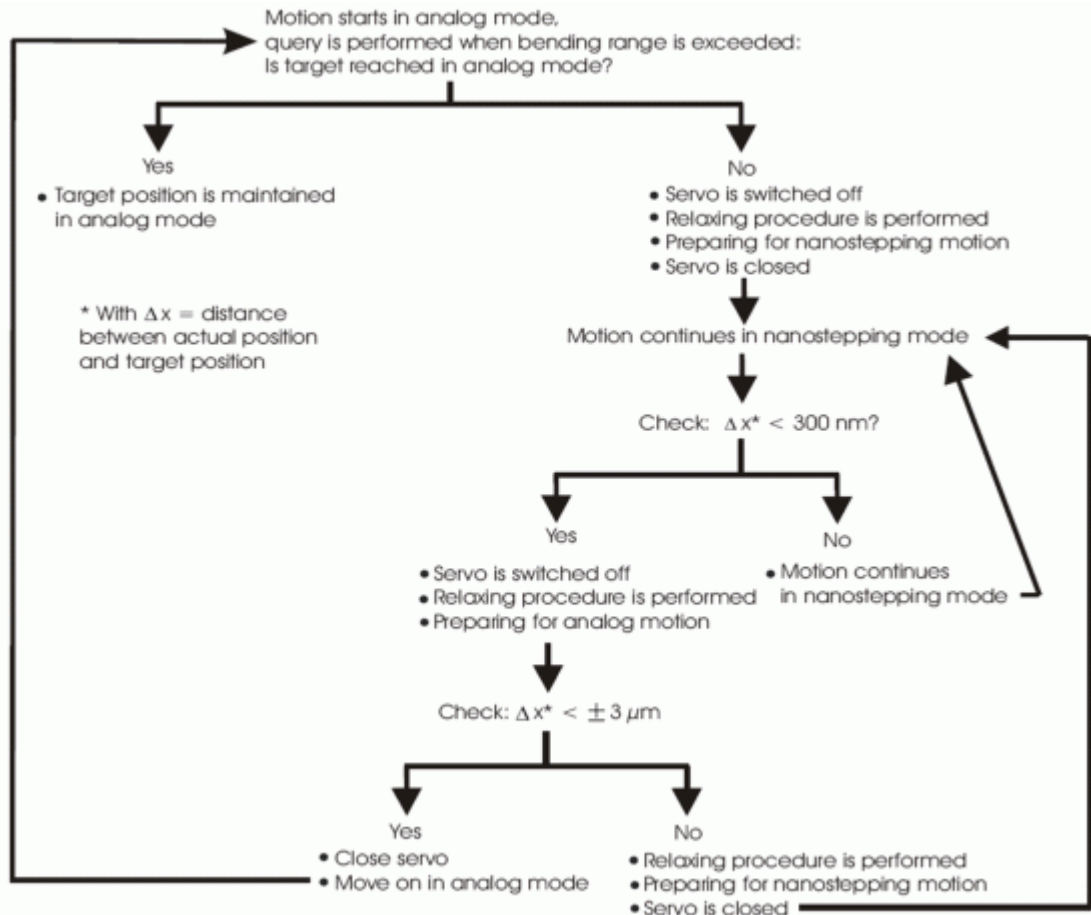


Figure 10: Closed-loop motion sequence with changes from analog mode to nanostepping mode and vice versa

Sequence of Transitions and States

With alternating motion modes, transitions and states performed are as described below:

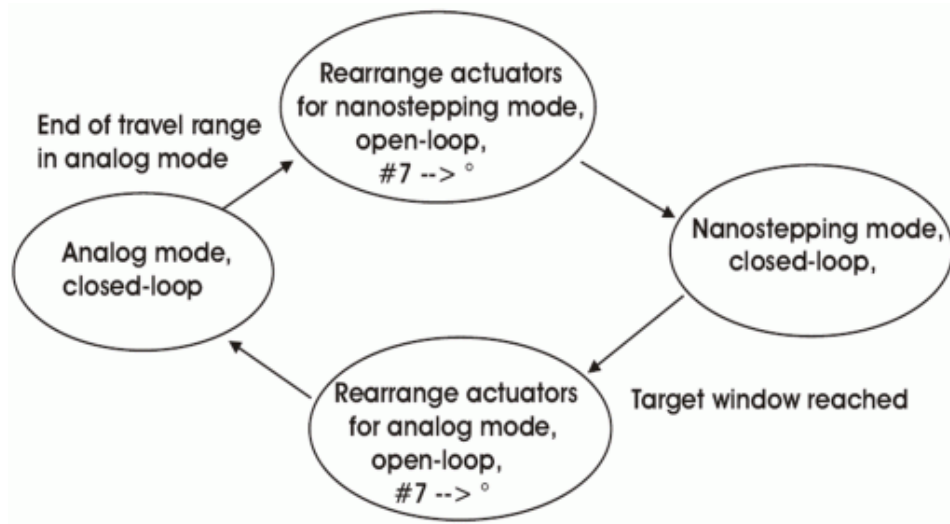


Figure 11: State machine for alternating motion modes

#7 command (p. 116) queries if the controller is ready to perform a new command. The response ° means that the controller is busy during both rearranging-the-actuators steps.

The steps illustrated in the figure above consist of the transitions and states as listed below. The numbers in brackets give the transition state (bits 8 to 11 in the response SRG? <AxisID>, see SRG? command (p. 178)).

■ *Rearrange actuators for nanostepping mode* consists of :

Relaxing transition (1)

Relaxed state (3)

Go to motion state (5)

A delay time set by parameter ID 0x7000004

■ *Nanostepping mode* consists of:

In motion state (4)

■ *Rearrange actuators for analog mode* consists of:

Relaxing transition (1)

Relaxed state (3)

Go to analog state (2)

A delay time set by parameter ID 0x7000004

- *Analog mode* consists of:

Analog state (0)

5.3.5 Application Notes

Sending an RNP command brings the NEXACT® linear drive to a full-holding-force, zero-drive-voltage Relaxed state.

Depending on the application conditions and parameter settings sending an RNP command causes a positional error of a few tens of nanometers up to one micrometer.

After switching from closed-loop to open-loop operation using the SVO command, the open-loop motion commands (OAD (p. 155), OSM (p. 163), OMA (p. 158), OMR (p. 161)) can be sent immediately.

After open-loop analog motion was done with OAD, an RNP command (p. 168) must be sent before servo can be switched on with SVO.

In open-loop operation, an RNP command must be sent each time the motion mode is to be changed from nanostepping (OSM, OMA, OMR) to analog (OAD) motion and vice versa.

The following actions can take up to four times the slewrate value (parameter ID 0x7000002):

- Switching servo on or off
- The first OAD after a change of motion mode
- The first OSM or OMA or OMR after a change of motion mode
- The RNP procedure

If a required transition between different motion modes was omitted, the E-861 sends an error message.

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) or the SRG? command (p. 178). With #7 (p. 116), you can query if the controller is ready to perform a new command. If the controller responds with °, it is not ready.

While a joystick connected to the E-861 is enabled with the JON command (p. 145), the servo can be switched on or off for the axis, and no transition is required. The axis can be controlled immediately by the joystick.

The recommended maximum step frequency for NEXACT® drives is 800 Hz. This applies to continuous operation. For short periods it is also possible to work with higher frequencies (see considerations regarding velocity in the Glossary of the included N310T0011 Technical Note with details about the NEXACT® Technology).

5.4 Control Basics

In this section you find information about the following items:

- Control value generation for both servo modes
- Trajectory generation
- Control algorithm
- Motion error handling

5.4.1 Control Value Generation

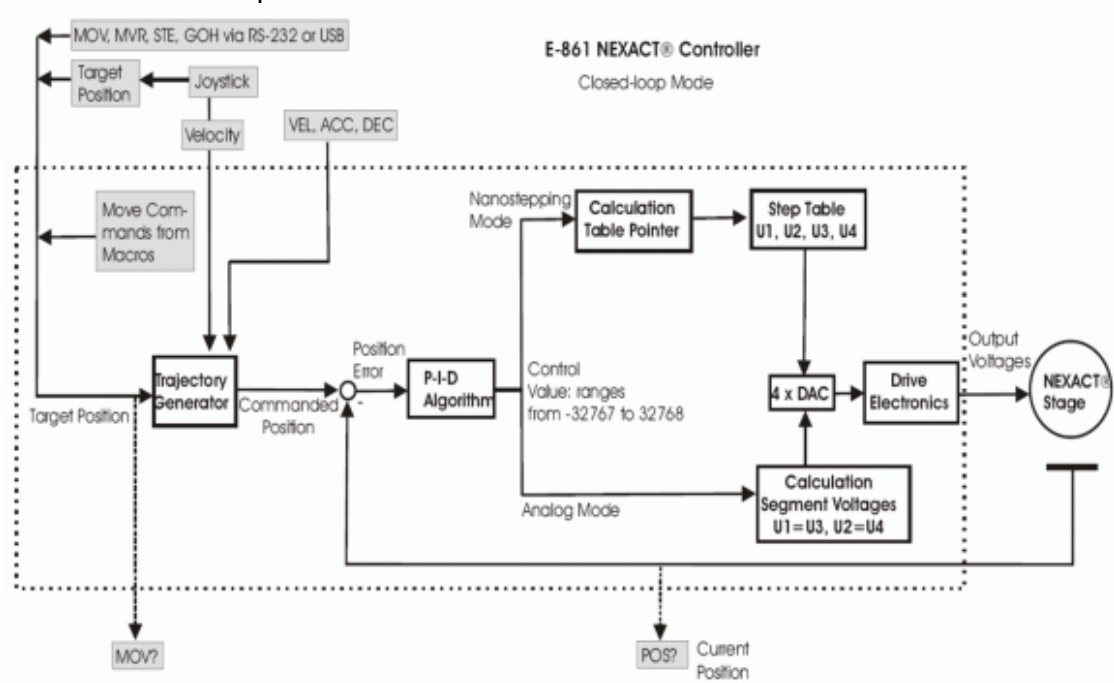
The E-861 features closed-loop and open-loop servo modes for control of the connected mechanics. The servo mode can be selected with the SVO command (p. 183).

You can query the current servo mode using the SVO? command (p. 185) or with the #4 (p. 114) and SRG? commands (p. 178) which have a bit-coded response.

Open-loop mode is active after power-on. Using a start-up macro, you can set up the device to start with closed-loop mode. The macro feature allows defining command sequences and storing them permanently in non-volatile memory in the controller. In addition to the servo mode setting you can, for example, program conditional execution of motion. See "Working with Controller Macros" (p. 82) for more information.

■ Closed-loop mode (servo on)

The block diagram below shows how the E-861 generates the output voltage for the connected axis (NEXACT® stage) from given input for closed-loop mode.



NEXACT® stages are generally operated in closed-loop mode. With the E-861, a trajectory generator calculates the motion profile from the given target position, velocity, acceleration and deceleration.

The position error resulting from the difference of the generated trajectory and the current position (sensor feedback) is passed through a proportional-integral-differential (P-I-D) algorithm. The result is the control value for the drive electronics integrated in the E-861.

With the E-861 closed-loop motion can be performed either as nanostepping motion or as a mix of analog mode motion and nanostepping motion. Therefore there are two PID parameter sets, one for nanostepping motion and one for analog motion.

See "PiezoWalk Driving Mode" (p. 63) for how to activate automatic alternating of motion modes and details regarding the PiezoWalk Driving mode's motion sequence.

With nanostepping motion the control value is in a range of -32767 to 32768. This value is processed so as to provide a constant input to the drive electronics (by an integration step) and to obtain a residual value between -32767 to 32768 as input for a step table.

This step table provides the four segment voltages U1 to U4. These are responsible for the motion of the piezo segments in the NEXACT® drive.

See also "Motion Modes" (p. 56) or read the N310T0011 Technical Note delivered with the controller for further details regarding the

nanostepping motion sequence and how segment voltages are formed.

With analog motion the control value range of -32767 to + 32768 is used according to the bending motion. Here, segment voltages U1 equals U3 and U2 equals U4.

You can use the following move commands:

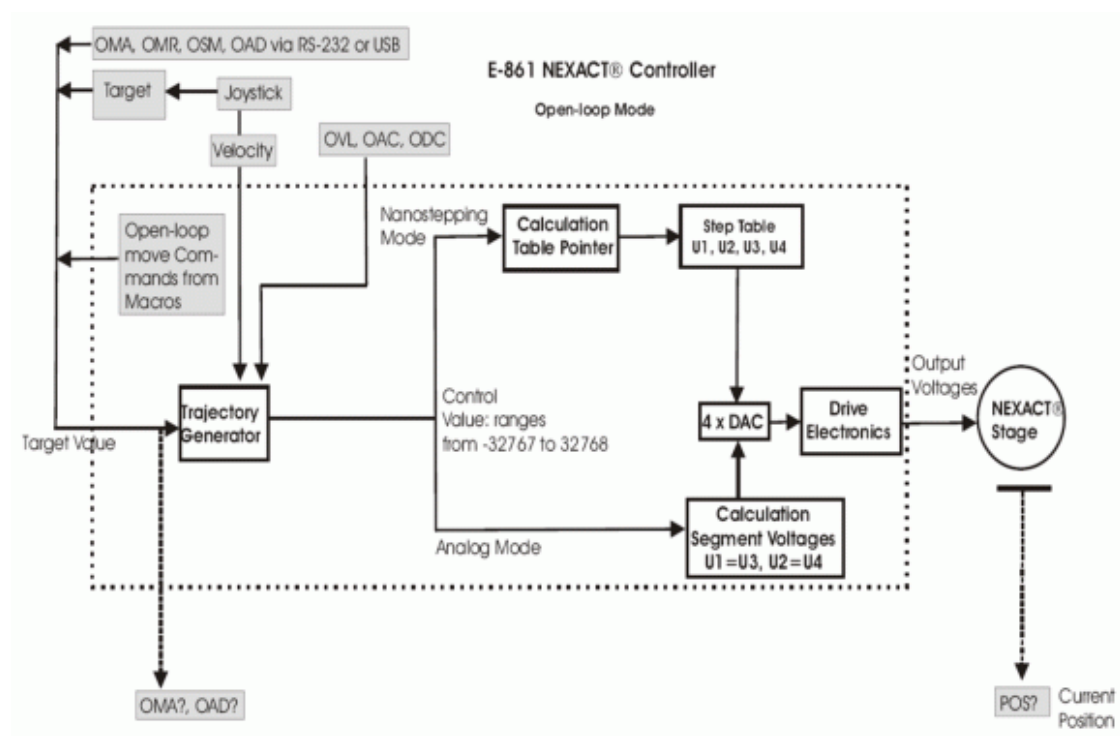
for usual moves: MOV (p. 151), MVR (p. 153), GOH (p. 135),
 STE (p. 181)

for reference moves: FNL (p. 129), FPL (p. 131), FRF (p. 133)

for hardware evaluation: FED (p. 128)

■ Open-loop mode (servo off)

The block diagram below shows how the E-861 generates the output voltage for the connected axis (NEXACT® stage) from given input for open-loop mode.



The open-loop mode omits servo-control algorithm. With open-loop mode motion can be performed as nanostepping motion using the OSM (p. 163), OMA (p. 158) and OMR (p. 161) commands or as analog motion using the OAD (p. 155) command.

Note that OMA and OMR commands can only be used if your system features a sensor, otherwise the connected mechanics can run into the hard stop at full speed.

The commanded open-loop target can be queried using OMA? (p. 160)

respectively OAD? (p. 157).

With open-loop mode, you can also use the following move commands:

for reference moves: FNL (p. 129), FPL (p. 131), FRF (p. 133)
for hardware evaluation: FED (p. 128)

Before absolute targets can be commanded (MOV, OMA), the mechanics must be referenced. Depending on the reference mode setting, even relative moves require referencing. See "Referencing" (p. 51) for details.

Joystick operation is possible with both closed-loop and open-loop operation.

While a joystick connected to the E-861 is enabled with the JON command, this joystick controls the axis velocity ("commanded velocity" output by the trajectory generator). During joystick control, the target position is set to the travel range limits given by the Max_Travel_Range_pos and Max_Travel_Range_neg parameters (0x15 and 0x30, see "Travel Range Adjustment" (p. 92) for more information). When disabling a joystick, the target position is set to the current position for joystick-controlled axes. For further joystick-related commands see the "Joystick Control" (p. 79).

See "Motion Modes" (p. 56) for a short description of the nanostepping and analog motion.

5.4.2 Trajectory Generation

A trajectory generator performs calculations to determine the current position, velocity, acceleration and deceleration of the axis at any given moment in time ("motion profile"). These values are called the commanded values (see also "Control Value Generation" (p. 68)).

The profile that is created by the trajectory generator of the E-861 depends on the motion parameters given by corresponding commands, by controller parameters and/or by a joystick:

Motion Parameter	Corresponding Commands	Corresponding Controller Parameter	Notes
Acceleration (A)	ACC (p. 118), ACC? (p. 118) for closed-loop mode	Current closed-loop acceleration (parameter ID 0xB; user unit/s ²) Changed by ACC or by SPA / SEP, can be saved with WPA	Limited by parameter 0x4A (Maximum closed-loop acceleration)
	OAC (p. 154), OAC? (p. 155) for open-loop mode	Current open-loop acceleration (parameter ID 0x7000202; step cycles/s ²) Changed by OAC command or by SPA /	Limited by parameter 0x7000205 (Maximum open-loop acceleration)

Motion Parameter	Corresponding Commands	Corresponding Controller Parameter	Notes
		SEP, can be saved with WPA	
Deceleration (D)	DEC (p. 119), DEC? (p. 120) for closed-loop mode	Current closed-loop deceleration (parameter ID 0xC; user unit/s ²) Changed by DEC (p. 119) or by SPA / SEP, can be saved with WPA	Limited by parameter 0x4B (Maximum closed-loop deceleration)
	ODC (p. 157), ODC? (p. 158) for open-loop mode	Current open-loop deceleration (parameter ID 0x7000203; step cycles/s ²) Changed by ODC command or by SPA / SEP, can be saved with WPA	Limited by parameter 0x7000206 (Maximum open-loop deceleration)
Velocity (V)	VEL (p. 188), VEL? (p. 189) for closed-loop mode	Current closed-loop velocity (parameter ID 0x49; user unit/s) Changed by VEL or by SPA / SEP, can be saved with WPA	Limited by parameter 0xA (Maximum closed-loop velocity) respectively by parameter 0x7000204 (Maximum open-loop velocity)
	OVL (p. 165), OVL? (p. 166) for open-loop mode	Current open-loop velocity (parameter ID 0x7000201; step cycles/s) Changed by OVL command or by SPA / SEP, can be saved with WPA	A joystick connected to the E-861 which is enabled with the JON command (p. 145) applies a factor to the current velocity set with VEL respectively OVL, see "Joystick Control" (p. 79) for details.
Target	MOV (p. 151), MVR (p. 153), GOH (p. 135), STE (p. 181) for closed-loop mode	-	A joystick connected to the E-861 which is enabled with the JON command (p. 145) sets the travel range limits

Motion Parameter	Corresponding Commands	Corresponding Controller Parameter	Notes
	OMA (p. 158), OMR (p. 161), OSM (p. 163) for open-loop mode		<p>as target position. When disabling a joystick, the target position is set to the current position for joystick-controlled axes. See "Joystick Control" (p. 79) for details.</p> <p>When the servo is switched on with the SVO command (p. 183) or when axis motion has been stopped with #24 (p. 117), STP (p. 182) or HLT (p. 137), the target position is set to the current position.</p>

Note that with open-loop mode the dimensions use step cycles instead of, e.g., μm .

Furthermore, be aware that the distance achieved by step cycles in open-loop is not as reproducible as a distance commanded in closed-loop mode: with open-loop changing conditions such as changed load or motion direction are not compensated by a servo loop.

The trajectory generator of the E-861 supports trapezoidal point-to-point profiles only: the axis accelerates linearly (at the given acceleration value) until it reaches the given velocity. It continues in motion at that velocity, then decelerates linearly (using the deceleration value) until it stops at the specified target position.

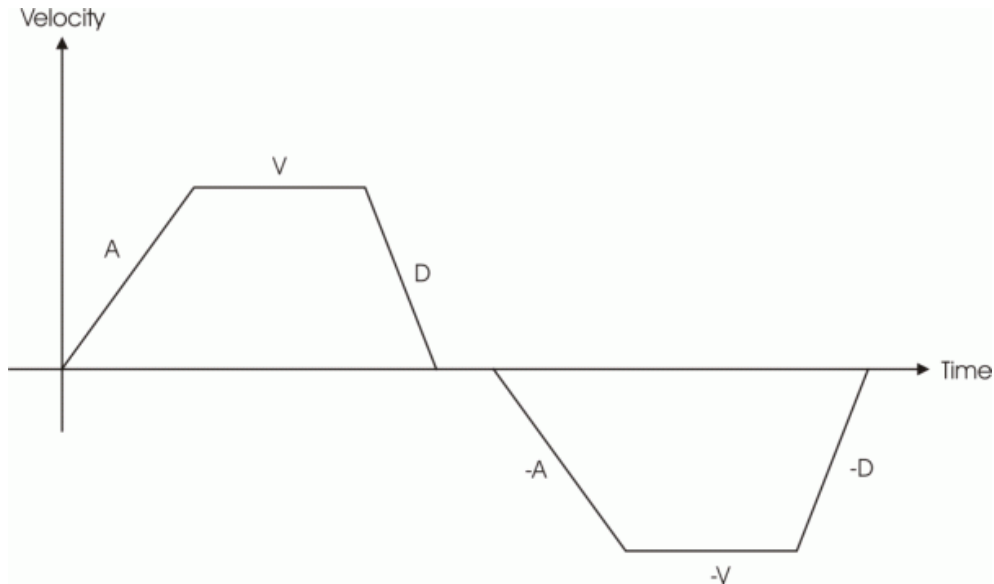


Figure 12: Simple trapezoidal point-to-point profiles, A = acceleration, D = deceleration, V = velocity

If deceleration must begin before the axis reaches the given velocity, the profile will have no constant velocity portion, and the trapezoid becomes a triangle.

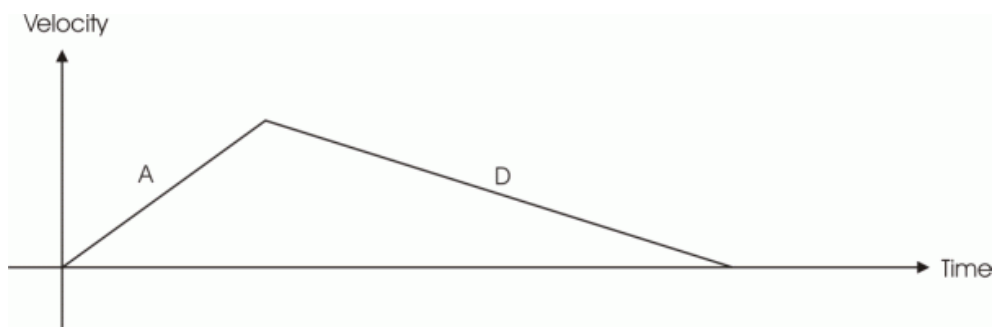


Figure 13: Simple trapezoidal point-to-point profile, A = acceleration, D = deceleration, no constant velocity

The slopes of the acceleration and deceleration segments may be symmetric (if acceleration equals deceleration) or asymmetric (if acceleration is not equal to deceleration).

The acceleration parameter is always used at the start of the motion. Thereafter, the acceleration value will be used when the absolute velocity is increasing, and deceleration will be used when the absolute velocity is decreasing.

If no motion parameters are changed during the motion then the acceleration value will be used until the maximum velocity is reached, and the deceleration value will be used when ramping down to zero.

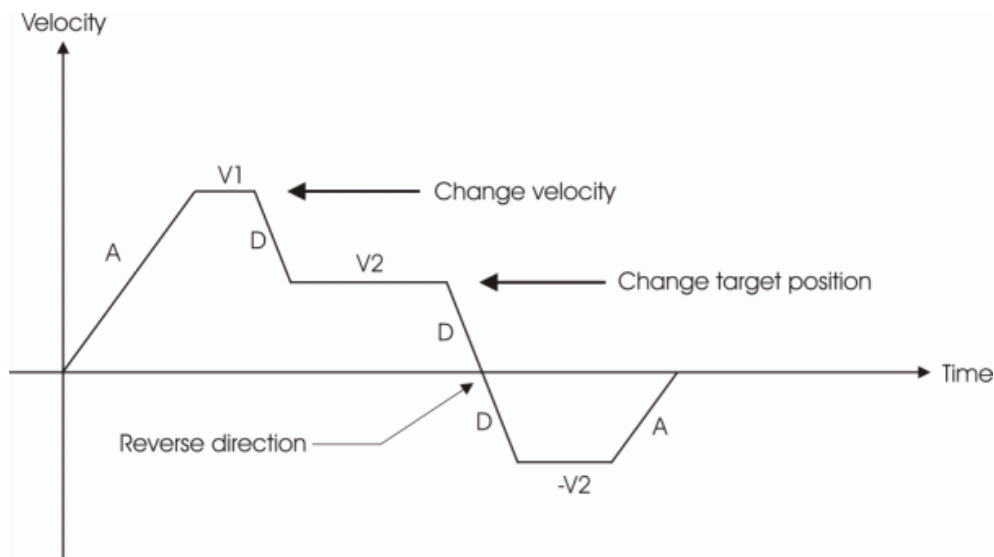


Figure 14: Complex trapezoidal profile, showing parameter changes; A = acceleration; D = deceleration; V1, V2, -V2 = velocities

It is acceptable to change any of the motion parameters while the axis is moving. The profile generator will always attempt to remain within the legal bounds of motion specified by the parameters.

If, during the motion, the target position is changed in such a way that an overshoot is unavoidable, the profile generator will decelerate until stopped, then reverse direction to move to the specified position.

5.4.3 Control Algorithm

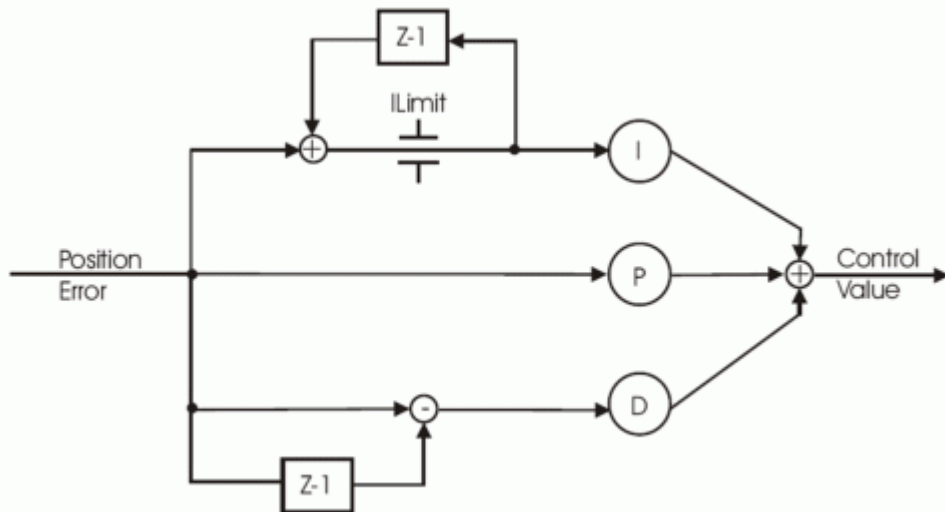


Figure 15: P-I-D algorithm with offset compensation

The E-861 controller for NEXACT® stages uses a proportional-integral-differential (P-I-D) algorithm.

See "Tuning the PID Control Parameters" (p. 95) for how PID control parameters can be adjusted.

The controller features two sets of PID parameters. One is used if nanostepping motion is performed. The second is used for analog motion:

- PID parameter IDs for nanostepping mode are:

- 0x1 for P-term
- 0x2 for I-term
- 0x3 for D-term

- PID parameter IDs for analog mode :

- 0x401 for P-term
- 0x402 for I-term
- 0x403 for D-term

NOTE

The PID set for analog motion is only active if the automatic alternating of motion modes is activated by the PiezoWalk Driving mode parameter (ID 0x7001A00) and if stage is in analog motion.

See "PiezoWalk Driving Mode" (p. 63) for further information about alternating motion modes.

See also "Controller Parameters" (p. 35) for detailed parameter descriptions and parameter handling.

When you are working with the host software from PI, you can select your stage type from a database which contains, amongst others, initial values for the parameters of the P-I-D algorithm.

The host software will then send the appropriate parameter values to the controllers volatile memory. See also "How to Store Parameter Settings" (p. 37) and "How to Create a New Stage Type in the PI Stages Database" (p. 98) for more information.

5.4.4 Motion Error Handling

Under certain circumstances, the current axis position (position feedback) may differ from the commanded position by an excessive amount. Such an excessive position error can indicate a potentially dangerous condition such as drive or encoder failure.

With the E-861 in closed-loop mode, it is possible to detect an excessive position error in the form of a "motion error" (error code: -1024).

The "motion error" criterion is given by the Maximum position error parameter (ID 0x8). You should set that parameter to the maximum position error which is tolerable in your application.

See "Controller Parameters" (p. 35) for more information on how to change parameter values.

If the position error falls out of the window formed by the Maximum position error parameter, the servo is switched off automatically for the axis concerned, all motion is stopped immediately, and error code -1024 is set (see figure below). Proceed as follows in case of a motion error:

- 1 Get the code of the last occurred error. In case of a motion error the response is -1024. The query resets the error to 0.
- 2 Check your hardware and make sure that it is safe for the stage to move the axis.
- 3 Switch the servo on for the axis using the SVO command (p. 183). This sets the target position to the current position of the axis.

The axis is now able to move again, and you can command a new target position.

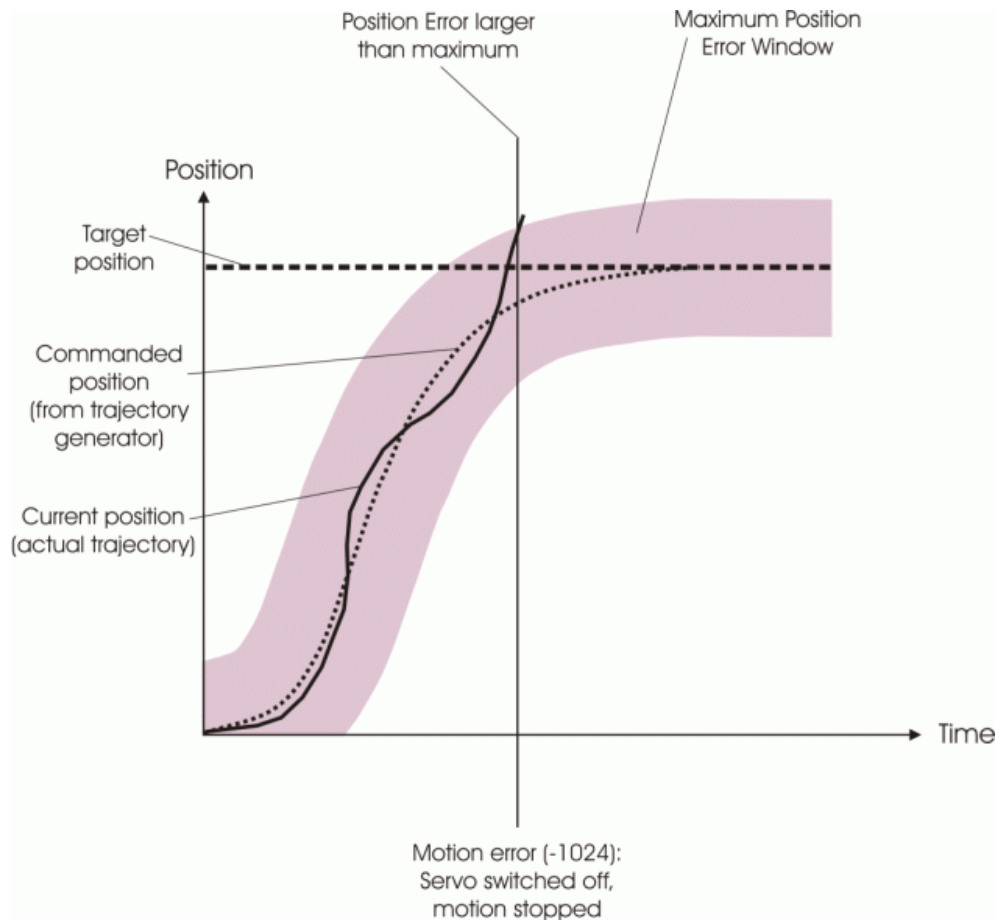


Figure 16: Motion error handling

6 Joystick Control



CAUTION

Do not enable a joystick via command when no joystick device is connected to the controller hardware. Otherwise the corresponding controller axis may start moving and could damage your application setup.

NOTE

Before a joystick can be operated correctly, a calibration routine may need to be performed. Activating the joystick before calibration may cause the axis to start moving even though the joystick is in the neutral position.

To calibrate a joystick axis of C-819.20 turn the corresponding "Adjust" knob on the joystick until the axis stops.

E-861 controllers offer convenient manual motion control. One C-819.20 analog joystick device can be connected to the Joystick socket (p. 220) of the E-861. The E-861 supports one axis and one button of the joystick device. See "Accessible Items and Their Identifiers" (p. 53) for the joystick related identifiers to use in commands.

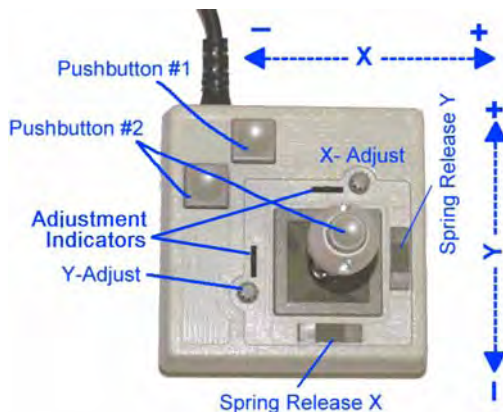


Figure 17: C-819.20 joystick device

The two joystick axes of an C-819.20 joystick device can be connected through the C-819.20Y cable to two E-861 controllers. In this case, on both controllers the joystick axis 1 must be selected for operation (the Y-cable maps the signals internally). If the "Axis Y" branch of the Y-cable is to be used, the "Axis X" branch must also be connected to a controller to provide

the supply power for the joystick device.

When a joystick is connected directly to the controller, it is the velocity of the motion axes that is determined by the displacement of the corresponding joystick axes.

For each joystick axis there is a lookup table that defines the velocity response for a certain amplitude of the joystick axis. The values in the lookup table are factors which will during joystick control be applied to the velocity set with VEL (p. 188) (closed-loop operation) or OVL (p. 165) (open-loop operation) for the controller axis, the range is -1.0 to 1.0.

To change a lookup table, you can load default profiles provided by the controller, or you can write a custom profile to the lookup table point-by-point (256 values).

While a joystick is active on a controller axis which is equipped with a position sensor, it is possible to switch from open-loop to closed-loop operation and vice versa with the SVO command (p. 183).

When disabling a joystick, the target position is set to the current position for joystick controlled axes which are in closed-loop operation.

Commands for joystick handling:

JON (p. 145)	<p>Enables or disables a specified joystick device for joystick operation.</p> <p>While a joystick is active on a controller axis, move commands are neither accepted from the command line nor from macros for that axis.</p>
JON? (p. 145)	Queries the current activation state of the joystick devices.
JAX (p. 139)	<p>Sets the controller axis which is to be controlled by a joystick axis.</p> <p>Each axis of a controller can only be controlled by one joystick axis.</p>
JAX? (p. 140)	Queries the current assignment of controller axes to joystick axes.
JAS? (p. 138)	Queries the current status of joystick axes. The response corresponds to the current displacement of the joystick axis and is the factor which is currently applied to the current valid velocity setting of the controlled motion axis, according to the lookup table.
JBS? (p. 140)	Queries the current status of joystick buttons. The response indicates if the joystick button is pressed; 0 = not pressed, 1 = pressed.

JDT (p. 141)	<p>Sets predefined lookup-table types for the joystick axes.</p> <p>The current lookup-table content for the specified joystick axis is overwritten by the selection made with JDT.</p> <p>The E-861 provides the following lookup-table types for special applications:</p> <p>1 = linear (power-on default) 2 = parabolic</p>
JLT (p. 142)	<p>Fills the lookup table for a joystick axis point-by-point. This overwrites the current lookup table content for this joystick axis. See the command description for an example.</p>
JLT? (p. 143)	<p>Reads the current lookup-table values.</p>

7 Working with Controller Macros

The macro feature allows defining command sequences and storing them permanently in non-volatile memory in the controller. Each defined macro can be called up by its own user-defined name.

In addition, it is possible to define a macro that will be executed automatically every time the E-861 is started, making possible stand-alone operation without a host computer. See the subsections below and the MAC command (p. 146) description for more details and examples.

NOTE

Macros can only be real-time processed if controller is not busy with extensive communication, as e.g. reading out the data recorder. The more commands are sent during performance of a macro the less real-time processing of the macro is possible.

NOTE

PIMikroMove offers a comfortable macro editor on the *Controller macros* tab card. Furthermore, PIMikroMove offers the "Host macro" feature which makes it possible to save macros on the host PC.

7.1 Defining Macros

To define a macro command sequence, first activate macro recording mode with the command MAC BEG <macroname> where <macroname> is a user-settable name with a maximum of 8 characters. While in macro recording mode, commands are not executed but stored in macro storage. Recording mode is exited by the MAC END command.

A macro can call another macro. Further nesting is not allowed (only one nesting level). A macro can call itself to form an infinite loop.

During macro recording no macro execution is allowed.

A macro can be overwritten by a macro with the same name.

A running macro sends no responses to any interface. This means questioning commands are allowed in macros but not answered and therefore useless.

The following commands provided by the E-861 can only be used in macros:
DEL (p. 120), MEX (p. 149) and WAC (p. 189). Using MEX and WAC, it is possible to set stop conditions or conditions for further macro processing.

Macro recording is possible when a joystick is active on the axis.

Example 1 (for a system with position sensor): Note how macro3 calls macros #1 and #2 for execution.

```
MAC BEG macro1
MVR 1 12.5
WAC ONT? 1 = 1
MAC END

MAC BEG macro2
MVR 1 -12.5
WAC ONT? 1 = 1
MAC END

MAC BEG macro3
MAC START macro1
MAC START macro2
MAC END
```

During macro recording for a controller whose address is different from 1, the address must as target ID be part of each command line to be recorded, but will not become part of the macro content.

Example 2 (for a system with position sensor): The controller address is set to 2 with the DIP switches. Macro addrtest is to be recorded:

```
2 MAC BEG addrtest
2 SVO 1 1
2 DEL 1000
2 FRF 1
2 MAC END
```

Now you can check the content of macro addrtest by sending

```
2 MAC? addrtest
```

The answer is

```
SVO 1 1
DEL 1000
FRF 1
```

i.e. the target ID has not become part of the macro.

See "Target and Sender Address" (p. 110) for more information.

7.2 Starting Macro Execution

A defined macro can be run by the command `MAC START <macroname>` where `<macroname>` is the name that was given to the macro to be run.

To run a macro multiple times, call it with `MAC NSTART <macroname> n` where `n` gives the number of times the macro is to be run.

Simultaneous execution of multiple macros is not possible. Only one macro can be executed at a time.

Any commands can be sent from the command line when a macro is running. The macro content and move commands received from the command line may overwrite each other, and only the last move command will be executed, irrespective of its source.

Macro execution can be stopped from the command line with `#24` (p. 117), `STP` (p. 182) and `HLT` (p. 137).

A running macro may not be deleted.

Macro execution is not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

You can query with `#8` (p. 116) if a macro is currently running on the controller and ask for the names of currently running macros with the `RMC?` command (p. 168).

7.3 Start-Up Macro

With `MAC DEF <macroname>` it is possible to set the specified macro as start-up macro. This macro will be automatically executed with the next power-on or reboot of the controller.

Example (for a system with position sensor):

```
MAC BEG startcl
JON 1 0
SVO 1 1
DEL 1000
FNL 1
MAC END
MAC DEF startcl
```

In the example, axis 1 will after power-on be immediately ready for closed-loop operation since the startup macro switches the servo on and performs

a reference move to the negative limit switch.

To ask for the current start-up macro setting, send

MAC DEF?

To undo the current start-up macro selection, send

MAC DEF

i.e. omit <macroname>.

Deleting a macro with MAC DEL <macroname> does not delete the start-up macro selection.

7.4 Preparing for Stand-Alone Preparation

If you want to operate controller and a stage without a host PC you can do so by using macros.

Stand-alone operation is possible if you store macros as auto-start macros, i.e. the content of the macro is performed automatically after the controller is powered on.

For example, you can program a macro for motion within a fixed travel range or a macro to enable a joystick or a pushbutton box directly after booting the controller. Thus you can command motion flexible.

Before you start stand-alone operation you must make sure that the parameter settings stored in the controller's non-volatile memory are appropriate for the stage connected:

For example, the controller must recognize the reference switch (i.e. 0x14 must be 1) to be capable to perform referencing in an autostart macro. This is not possible with Default-Stage-N parameter settings in the controller's non-volatile memory.

See "Storing Parameter Settings to Non-Volatile Memory Using PIMikroMove Main Window" (p. 38) or "Storing Parameters to Volatile and Non-Volatile Memory via Commands" (p. 40), for instructions.



CAUTION

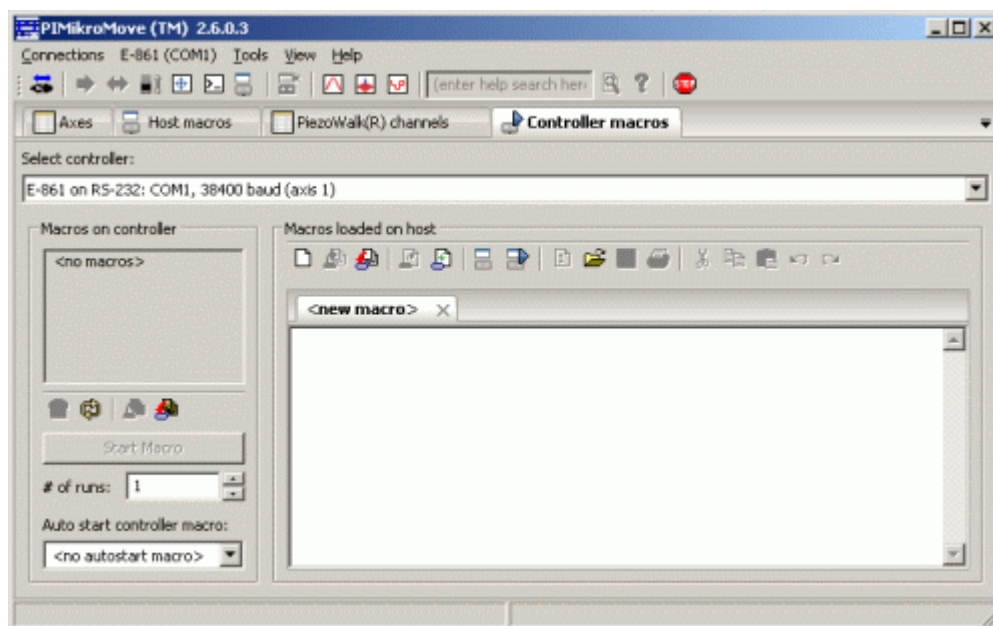
Do not enable a joystick via command when no joystick device is connected to the controller hardware. Otherwise the corresponding controller axis may start moving and could damage your application setup.

An example follows of how to generate a start-up macro that:

- Switches servo on
- References the stage
- Activates joystick operation

To generate the auto start macro as described proceed as follows:

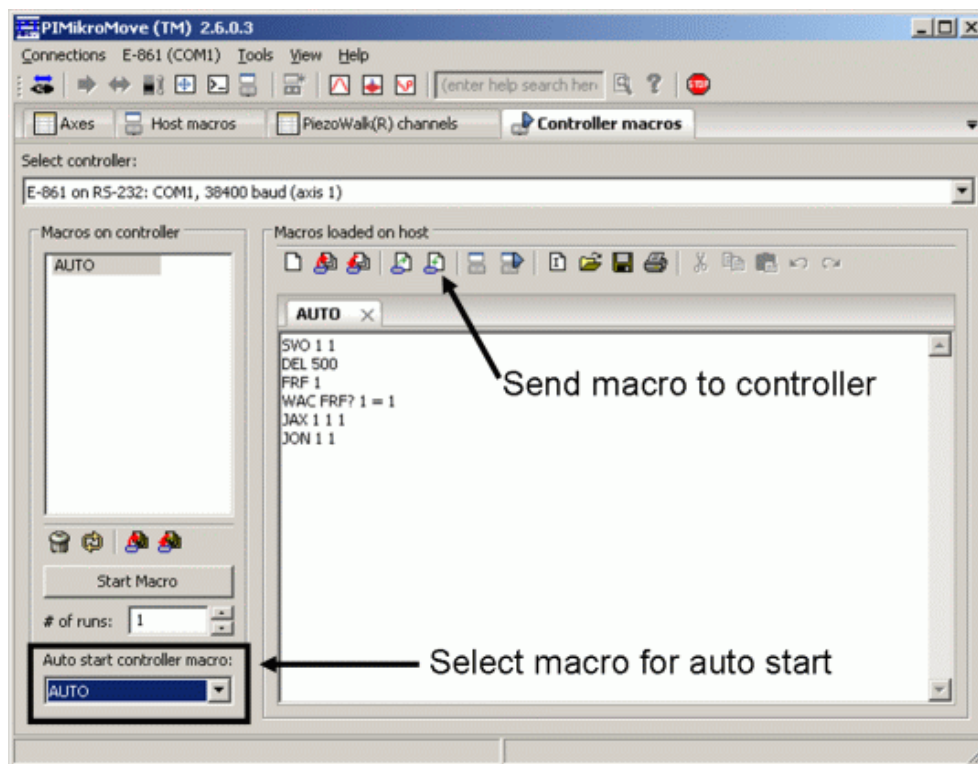
- 1 Select the *Controller macros* tab of the PIMikroMove main window, see next figure.



- 2 Insert a macro with the following commands:

```
SVO 1 1  
DEL 500  
FRF 1  
WAC FRF? 1 = 1  
JAX 1 1 1  
JON 1 1
```

- 3 Send macro to controller, see next figure.



- 4 Select macro for autostart, see figure above.
This macro will be executed automatically every time the controller is powered on or rebooted.

8 Data Recording

For general information regarding the data recording you can send the HDR? command (p. 135) which lists available record options and trigger options and gives additional information about data recording. The E-861 has 2 data recorder tables (ask with TNR? (p. 187)) with 1024 data points per table.

The data recorder configuration, i.e. the assignment of data sources and record options to the recorder tables, can be changed with DRC (p. 122), and the current configuration can be read with DRC? (p. 123). Data recorder tables with record option 0 are deactivated, i.e. nothing is recorded (power-on default).

Recording can be triggered in several ways. Ask with DRT? (p. 127) for the current trigger option and use DRT (p. 126) to change it. A trigger option set with DRT will become valid for all data recorder tables with non-zero record option. By default data recording is triggered when a step response measurement is made with STE (p. 181).

The record table rate can be set with the RTR command (p. 171). The power-on default of this value is one servo cycle (ask with RTR? (p. 172)). You can cover longer periods by increasing the record table rate.

Recording always takes place for all data recorder tables with non-zero record options.

Recording ends when the content of the data recorder tables has reached the maximum number of points.

The last recorded data can be read with the DRR? command (p. 124). The data are reported in GCS array format, for details regarding the GCS array see the separate manual (SM146E) which is provided on the E-861 CD. Reading can take long depending on the number of points to be read! It is possible to read the data while recording is still in progress.

When the controller is powered down, the content of the data recorder tables and all data recorder configuration and trigger settings are lost. The configuration and trigger settings are reset to their factory defaults on power on.

9 Customizing the System

This section contains information about:

- Which parameters you may have to change to adjust the controller to your individual application or to use a custom stage
- Which parameters you may adjust regarding travel range
- How to tune PID control parameters
- How you can generate a user-defined stage database entry

In addition, you find the following information for adjustment of the E-861 controller for a custom sensor:

- When to adjust servo loop input factor parameters
- How to adjust controller for a custom sensor that uses a custom interpolation board
- What sensor properties are required for using the controller's GEMAC interpolation board
- What to provide if a custom sensor is to use the controller's GEMAC interpolation board

Adjustment and storing of adjusted parameter settings can be required in the following cases:

If your application requires adjustment regarding:

- Travel range and/or a modified home position
- Physical units and axis unit

If you use a custom stage you have to provide for the following:

- The logic of your reference and limit switches must be reflected in the controller's parameter settings

- The parameters of your stage's sensor must match the GEMAC interpolation board's requirements. This interpolation board is part of the E-861 controller
- The resolution of your stage's sensor must be reflected by the servo-loop input factor

For instructions on how to store adjusted parameter settings to volatile and non-volatile memory read "How to Store Parameter Settings" (p. 37).
 For instructions on how to generate a custom stage database entry see "How to Create a New Stage Type in the PI Stages Database" (p. 98).
 See "Adjustment for Custom Sensor" (p. 99) for what to consider for operating the E-861 controller with a stage with custom sensor.

9.1 Parameters for Customizing

The properties of your mechanics (stage configuration, sensor, load) must be reflected in the corresponding parameters of the E-861 firmware. The following parameters may have to be adjusted depending on your application:

- Parameters which affect the travel range. These parameters are:

Parameter ID	Function
0x15	Maximum travel in positive direction
0x16	Position value at reference position
0x17	Distance between reference switch and negative limit switch
0x2F	Distance between reference switch and positive limit switch
0x30	Maximum travel in negative direction

See "Travel Range Adjustment" (p. 92) for details.

- The numerator and denominator of the counts-per-physical-unit factor (parameter IDs 0xE and 0xF) which determines the "user" unit for motion commands and the settings of all other parameters whose unit is based on the "user" unit
- Parameter for Axis unit (ID 0x7000601), since it is not adjusted automatically by the counts-per-physical-unit factor
- Further parameters if this is necessary for your application
- PID control parameters should be adjusted during closed-loop operation of the system until the system performance proves satisfactory, e.g. by measuring the step response of the system (STE

command and DRR? command (p. 124)).

The P, I and D values depend on the applied load and motion parameters (velocity, settling behavior).

See also "Tuning PID Control Parameters" (p. 95) for how PID control parameters can be adjusted.

The following parameters may have to be adjusted if you use a custom stage:

- Parameters for the limit and reference switches and their signal logic to make them fit to your hardware. These parameters are:

Parameter ID	Function
0x14	Stage has a reference switch 1 if yes, 0 if no
0x31	Invert the reference 1 if invert, 0 if no inversion
0x32	Stage has limit switches 0 if yes, 1 if no

- The E-861 is equipped with a GEMAC interpolation board for incremental measuring systems.
Check if your sensor hardware (encoder) is compatible with the preset values of the parameters for the GEMAC interpolation board (IDs 0x7000010 to 0x700001F).
See "GEMAC Parameters" (p. 105) for details.
- Parameters for numerator and denominator of the servo loop input factor (IDs 0x5A and 0x5B) are preset to 50000 counts per 1 mm. Needs to be adjusted only if your sensor resolution differs from 50000 counts per 1 mm.
See "Servo Loop Input Factor" (p. 99) for more information of this factor's function.

If you want to operate the controller with a custom stage not delivered from PI and if you use PI software, as e.g. PIMikroMove, you can use the Default-Stage-N's stage database entry, i.e. a given set of parameter settings.

Ensure that the parameter settings of Default Stage N correspond to your mechanics – make adjustments if necessary.

See "Controller Parameters" (p. 35) for how to handle parameter settings and how to store them.

9.2 Travel Range Adjustment

The figures below give a universal hardware scheme of a positioning stage with incremental sensor, reference and limit switches. To work with such a stage in closed-loop operation, the corresponding controller parameters must be adjusted properly (see "Controller Parameters" (p. 35) for how to modify parameter values).

In the example shown in the first figure, the travel range, i.e. the distance from negative to positive limit switch is 20 mm, the distance between the negative limit switch and the reference switch is 8 mm, and the distance between reference switch and positive limit switch is 12 mm (you can use the FED command (p. 128) in combination with the POS? command (p. 167) to identify the values). These hardware properties are represented by the following controller parameters in the E-861 firmware:

DISTANCE_REF_TO_N_LIM (parameter ID 0x17) = 8
DISTANCE_REF_TO_P_LIM (parameter ID 0x2F) = 12

To allow for flexible localization of the home position (0), a special parameter is provided. It gives the offset between reference switch and home position which is to be valid for the stage after a reference move (see below). In the example, the home position is to be located at the negative limit switch after a reference move, and hence the offset between reference switch and home position is 8 mm.

VALUE_AT_REF_POS (parameter ID 0x16) = 8

To allow for absolute moves, either an absolute "initial" position can be set with the POS command (p. 166), or the stage can perform a reference move to a known position where a defined position value will be set as the current position (see "Referencing" (p. 51) for further details). By default, a reference move is required. In the example, known positions for reference moves are given by the reference switch and the limit switches. Depending on the switch used for the reference move, a certain combination of the above-mentioned parameters is used to calculate the position to be set at the end of the move:

- Reference switch (FRF command (p. 133)): the stage is moved to the reference switch, and the value of VALUE_AT_REF_POS is set as the current position.
- Negative limit switch (FNL command (p. 129)): the stage is moved to the negative limit switch and the difference of VALUE_AT_REF_POS and DISTANCE_REF_TO_N_LIM is set as the current position (can be negative).

- Positive limit switch (FPL command (p. 131)): the stage is moved to the positive limit switch and the sum of VALUE_AT_REF_POS and DISTANCE_REF_TO_P_LIM is set as the current position.

It is furthermore possible to set "soft limits" which establish a "safety distance" which the stage will not enter on both ends of the travel range. In the E-861 firmware, those soft limits always refer to the current home position (0; in the example located at the negative limit switch after a reference move). The soft limits are to be deactivated in the example so that the corresponding parameters must be as follows:

MAX_TRAVEL_RANGE_POS (parameter ID 0x15) = 20 mm

MAX_TRAVEL_RANGE_NEG (parameter ID 0x30) = 0 mm

(This means that the stage can move 20 mm in positive direction, starting from the home position, and 0 mm in negative direction, starting from the home position.)

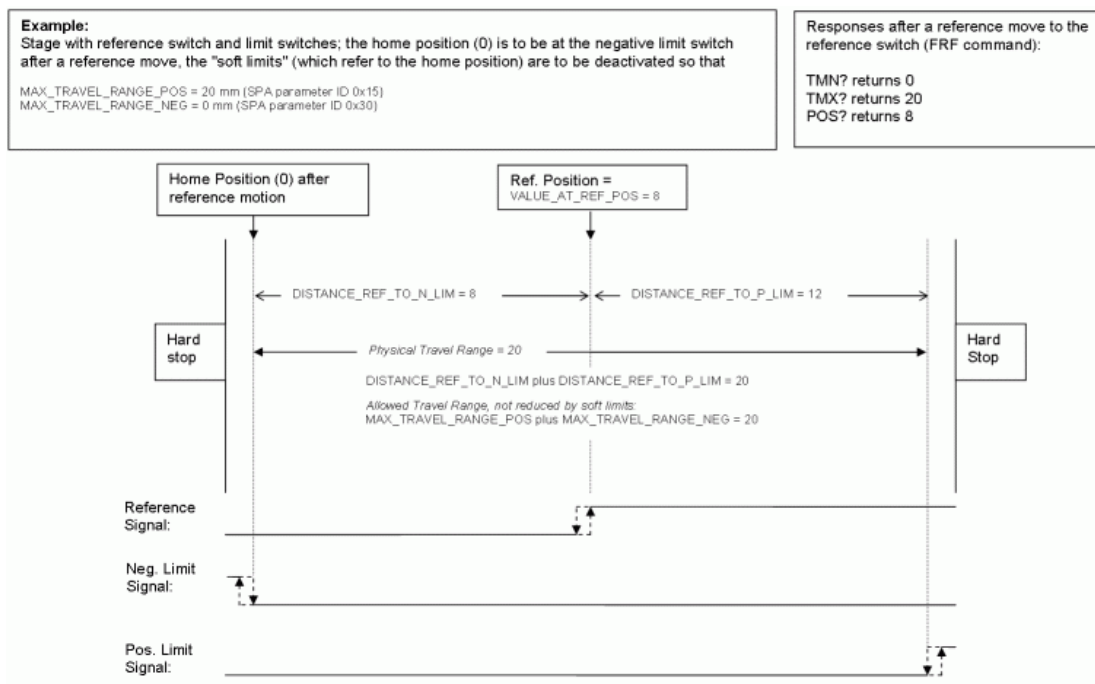


Figure 18: Positioning stage and corresponding controller parameters

Now in the same example, a "safety distance" is to be established on both ends of the travel range by setting soft limits, and the home position is to be located at about 1/3 of the distance between the new negative end of the travel range and the reference switch. The limit switches cannot be used for reference moves anymore.

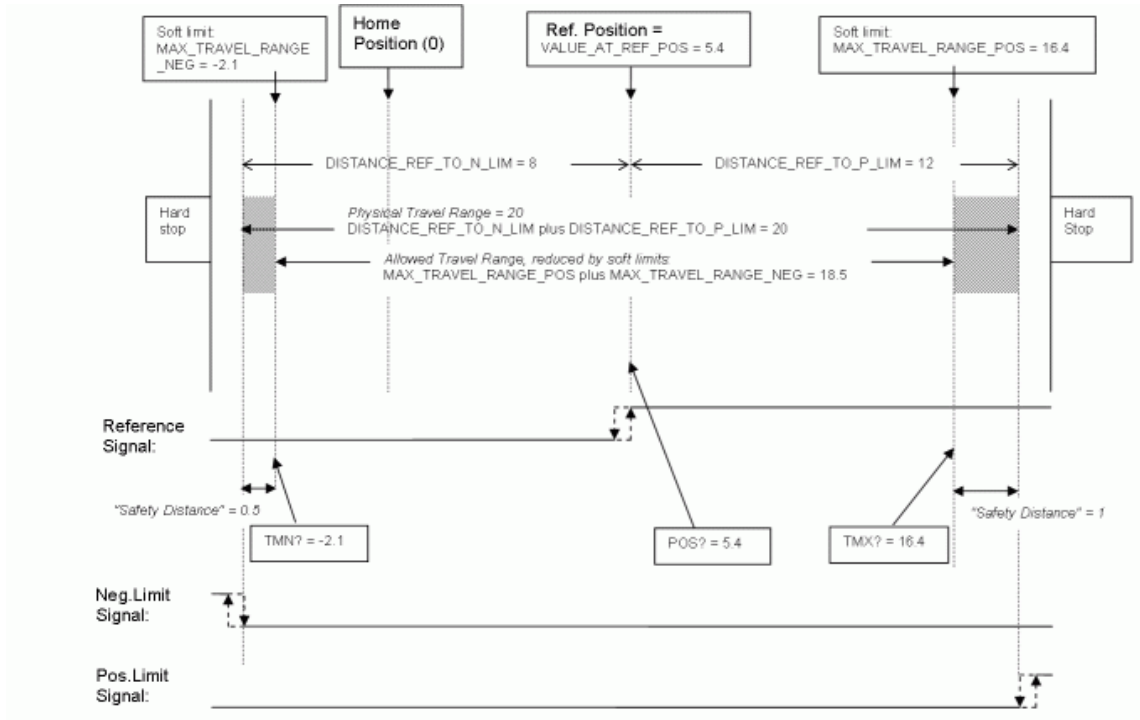


Figure 19: Positioning stage, soft limits set in the controller to reduce the travel range

After the stage was referenced again by moving it to the reference switch (FRF command), the following responses will be given:

TMN? (p. 186) returns -2.1
 TMX? (p. 187) returns 16.4
 POS? (p. 167) returns 5.4

CAUTION

If the soft limits (MAX_TRAVEL_RANGE_POS and MAX_TRAVEL_RANGE_NEG) are used to reduce the travel range, the limit switches cannot be used for reference moves. The FNL and FPL commands will provoke an error message, and only the reference switch can be used for a reference move (FRF).

Be careful when setting the values for VALUE_AT_REF_POS, MAX_TRAVEL_RANGE_POS and MAX_TRAVEL_RANGE_NEG because there is no plausibility check.

The soft limits may not be outside of the physical travel range:
 $\text{MAX_TRAVEL_RANGE_POS} \leq \text{DISTANCE_REF_TO_P_LIM} + \text{VALUE_AT_REF_POS}$
 $\text{MAX_TRAVEL_RANGE_NEG} \geq \text{VALUE_AT_REF_POS} - \text{DISTANCE_REF_TO_N_LIM}$

Otherwise, reference moves to the limit switches would have incorrect results because the values of the soft limits would be set at the end of the referencing procedure.

Be careful when referencing the stage by setting an initial absolute position with POS since the values for MAX_TRAVEL_RANGE_POS and MAX_TRAVEL_RANGE_NEG are not adapted. In the worst case, the soft limits will now be outside of the physical travel range, and the stage will no longer be able to move since the closed-loop move commands check the soft limit settings.

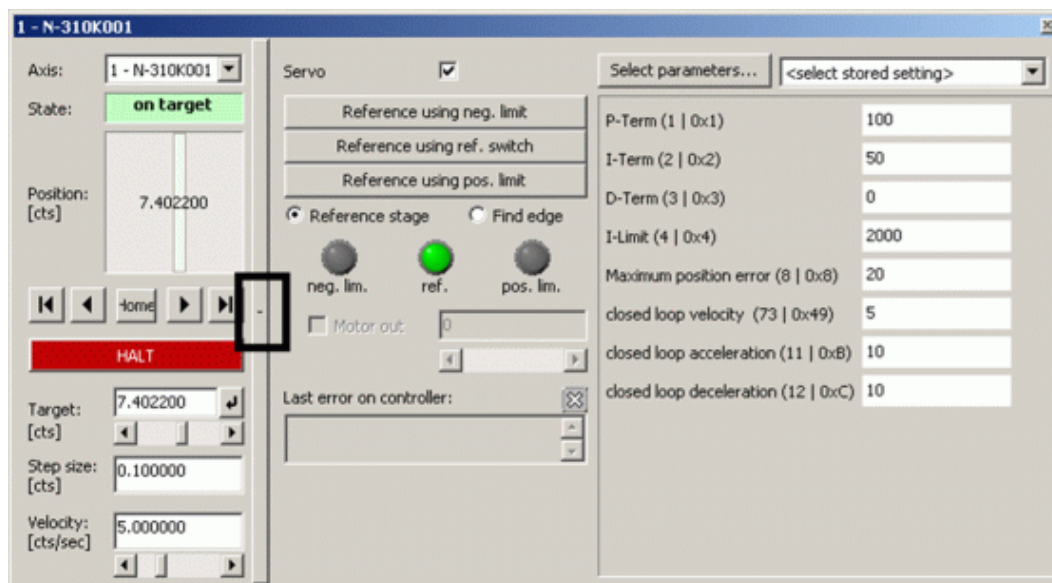
9.3 Tuning PID Control Parameters

If PID tuning is required it is recommended to use the controller's data recorder and PIMikroMove.

PIMikroMove main window must be open.

To adjust PID control parameters proceed as follows:

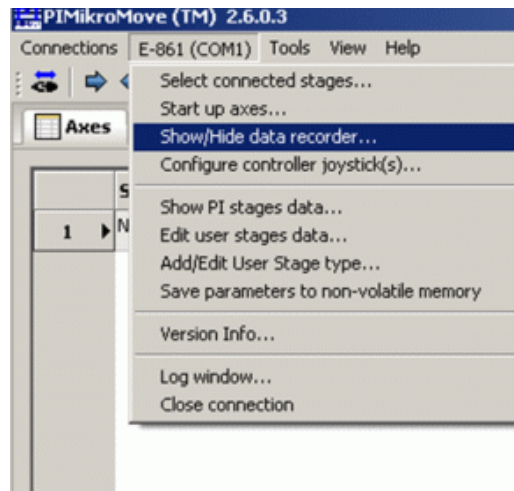
- 1 Open the expanded single axis window by following the *View → Single Axis Window* menu sequence for the connected stage.
- 2 Click on the + at the right side of the single axis window, see figure below.



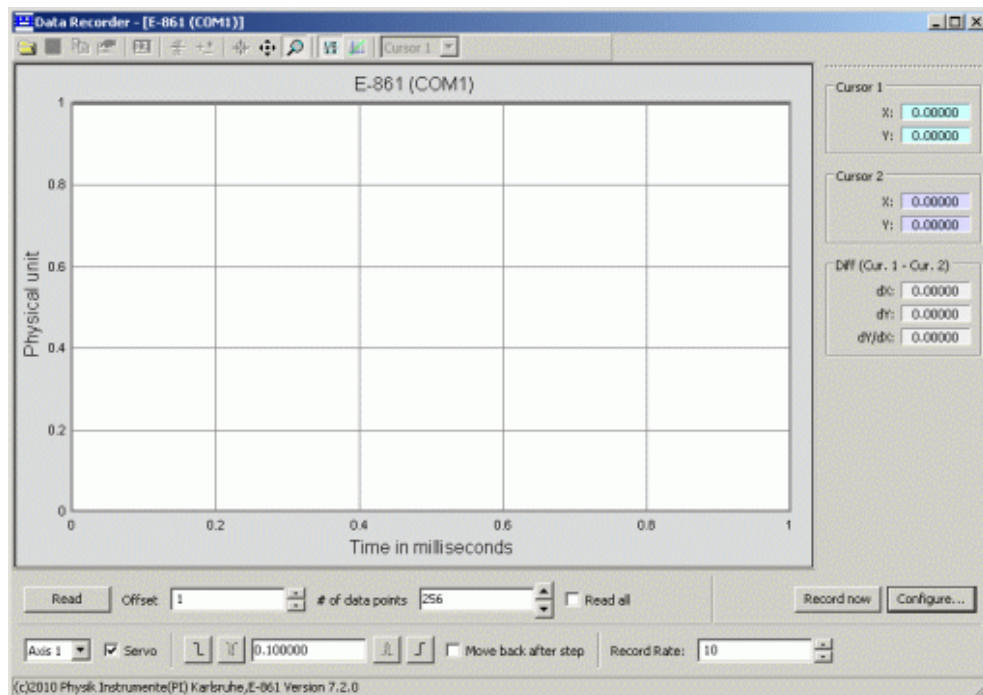
- 3 In the list at the right side of the expanded single axis window you can check the current settings and you may insert new settings. If a parameter you wish to adjust does not occur in the list click on *Select parameters* to display the parameter in the list.

Note that a new parameter setting is only sent to the controller after <ENTER> is pressed while the cursor is in the text entry.

- 4 To display a step response open the controller's data recorder. To do so follow the *E-861* → *Show/Hide data recorder* menu sequence, see figure below.



The *Data Recorder* window opens as shown in the next figure:



- 5 Configure the data recorder.
For detailed information read the following sections in the SM148E PIMikroMove Manual:

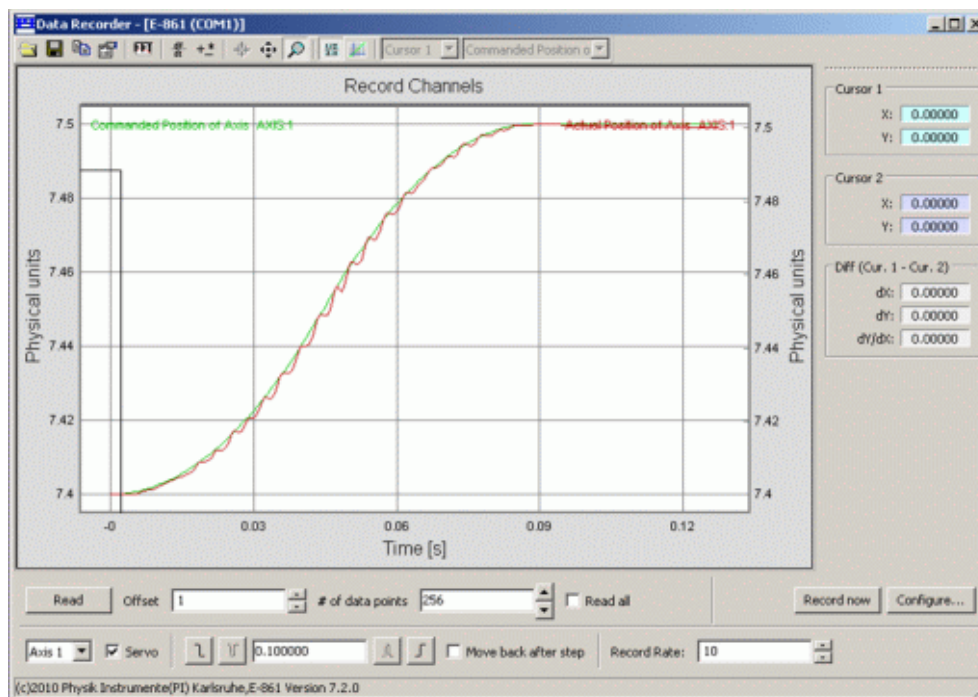
"Data Recorder"

"Configure Data Recorder"

"Perform Step or Impulse Measurements"

Make sure that data recorder settings are adjusted such as, for example, step size to be recorded, record rate and number of data points on the Data Recorder screen.

- 6 Press the step response button (positive slope) to start and record a step response.
See figure below for an example:



- 7 If the step response does not prove satisfactory, adjust the PID settings in the expanded *Single axis window*.
- 8 Press enter for each adjusted parameter setting in the expanded *Single axis window* separately.
- 9 Start and record another step response on the *Data Recorder* screen.
If the result is not satisfactory repeat steps 7 to 9 with different PID settings.

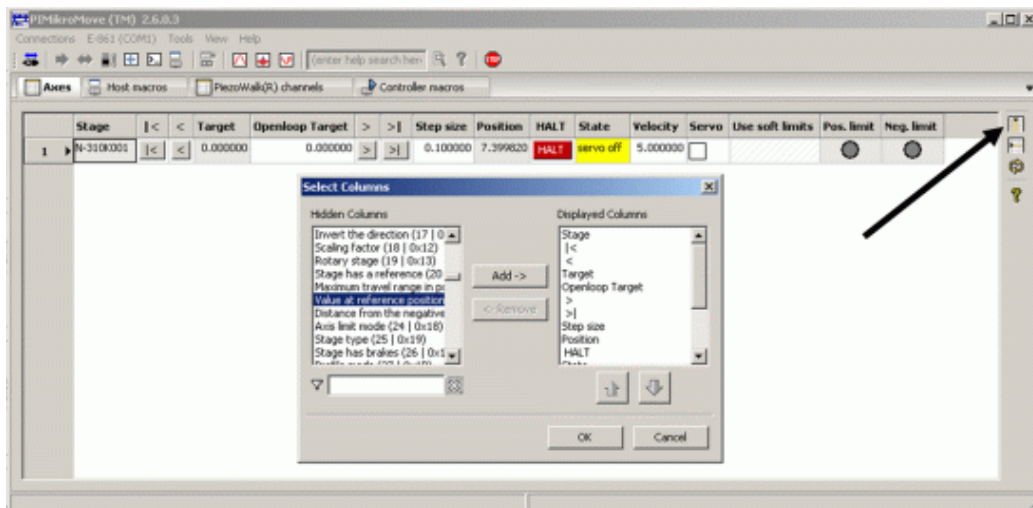
- 10 If you wish to read the position data of a step response in PIMikroMove's *Command entry* window send a DRR? command to read the data from the controller's data recorder.

9.4 How to Create a New Stage Type in the PI Stages Database

The easiest way to add a new stage type to the UserStages2 database is to modify the parameters of an existing stage type and save them under a new name. Thereafter you can select this newly defined stage in PIMikroMove or in other PI software as well.

Proceed as follows:

- 1 Assign the stage type that comes closest to your stage to the appropriate axis. See *Select connected stages* step, i.e. step 9, of the "Getting Started" (p. 12) section for how to do this. Afterwards the *Start Up Axes* dialog may open—you can close this dialog because at this point it is not necessary to reference the axis.
- 2 On the *Axes* tab card, display the columns for the parameters you want to modify. Press the *Select columns to be displayed* icon in the right top corner of the PIMikroMove main window, see next figure.



- 3 Change the values of the parameters you want to modify by typing them into the appropriate fields of the *Axes* tab card. Note that only fields with white backgrounds can be edited.

- 4 Save the modified settings as a new stage using the *Add/Edit User Stage type...* item from the corresponding controller menu. You simply have to define a new name for your stage and click *OK*.
- 5 The new stage is now displayed on the *Axes* tab card, and you can work with it (e.g. reference the stage: right-click on the axis row and select the *Start up axes...* item in the controller menu of the corresponding controller).

If you want to further modify the stage parameters, use the *Add/Edit User Stage Type* menu item again to save the changes.

9.5 Adjustment for Custom Sensor

E-861 controllers feature sensor boards with interpolation circuitry, that are adjusted to encoders of PI's NEXACT® drives.

If you use a custom stage with a custom sensor it is recommended to use also custom interpolation hardware suitable for that sensor.

See "Adjustment for Custom Sensor Using Custom Interpolation Board" (p. 100) for how to proceed for adjusting the controller hardware.

It is also possible to adjust the controller to a custom sensor using the GEMAC interpolation board.

See "GEMAC Parameters" (p. 105) for details about the GEMAC parameters.

See "Adjustment for Custom Sensor Using GEMAC Interpolation Board" (p. 106) for what you need to provide and what requirements must be fulfilled.

Details and instructions for the adjustment procedure are given in the E861T0008 Technical Note. Call your PI representative or write to info@pi.ws to ask for this Technical Note if required.

Irrespective of whether you use a sensor with its own interpolation circuitry or a sensor using the GEMAC interpolation board you have to make sure that the servo loop input factor matches the custom sensor's resolution.

See "Servo Loop Input Factor" below to find out if you have to adjust the corresponding parameters.

9.5.1 Servo Loop Input Factor

Parameters 0x5A and 0x5B represent numerator and denominator of the servo loop input factor. This factor decouples servo loop parameters from the encoder resolution.

This factor has to be adjusted only if a custom sensor with a resolution other than 50000 counts per 1 mm is to be used.

0x5A and 0x5B have to be set carefully to guarantee a stable control loop. See “How to Store Parameter Settings” (p. 37) for further details.

Note that the servo loop input factor formed by 0x5A and 0x5B is independent from 0xE and 0xF, i.e. the counts-per-physical-unit factor. The counts-per-physical-unit factor has no influence on control loop stability, but is used for input and output scaling of position values.

9.5.2 Adjustment for Custom Sensor Using Custom Interpolation Board

If you wish to use a drive with a custom specific sensor that features its own interpolation circuitry, you have to remove the GEMAC interpolation board and adjust the controller to process digital sensor, i.e. encoder, inputs.

To adjust the controller for a sensor with its own interpolation circuitry you have to provide the following items:

- A Phillips head screwdriver to remove/fix top plate from/to controller
- Sensor with interpolation circuitry that provides a sensor reference signal with TTL level and a minimum pulse length of more than 50 μ s
- Documentation of the sensor manufacturer for sensor calibration

In addition, you have to make sure that the servo loop input factor matches the custom sensor's resolution.

See “Servo Loop Input Factor” (p. 99) for details about this factor.

See “How to Store Parameter Settings” (p. 37) for details on how to store parameter settings to volatile and non-volatile memory of the controller.

DANGER

Procedures which require opening the case should be carried out by authorized, qualified personnel only.

Disconnect the controller from power when opening the case, and when resetting internal switches or jumpers.

When the controller must be operated with the case open, voltages of up to 48 VDC and currents of up to 2 A can be exposed. Do not touch internal conductors.



CAUTION

The boards inside the E-861 are ESD-sensitive (electrostatic discharge sensitive) devices. Observe all precautions against static charge

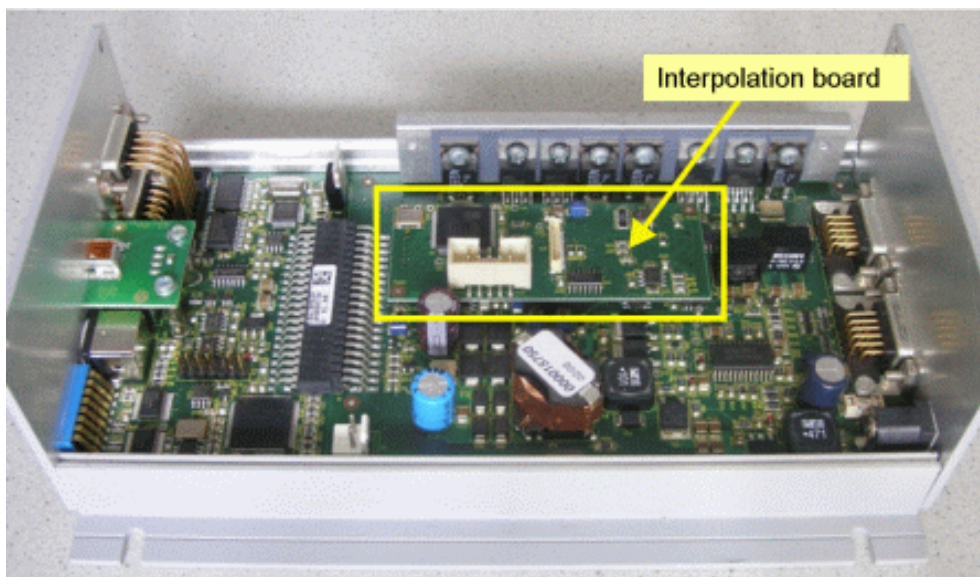


buildup before handling these devices. Avoid touching circuit components, pins and PCB traces. Discharge any static electricity you may have on your body by briefly touching a conductive, grounded object before you touch any electronic assembly.

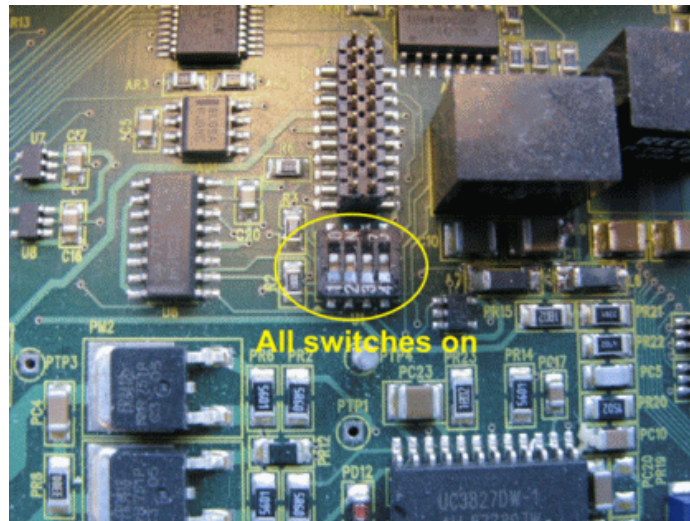
Make sure that no conductive particles of any kind (metallic dust or shavings, broken pencil leads, loose screws) contact the device circuitry.

To adjust the E-861 controller for sensor signals from a custom sensor which uses its own interpolation board proceed as follows:

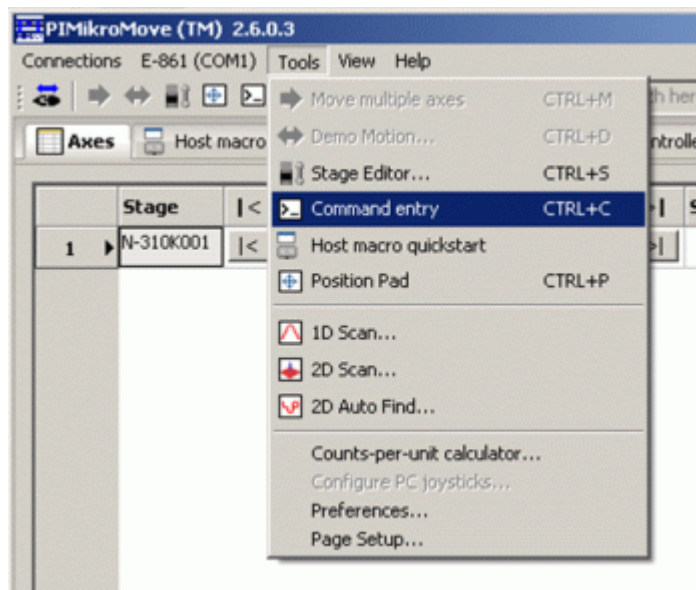
- 1 Disconnect the E-861 from the power supply to power it down.
- 2 Unscrew the 2x2 cross-head screws at the front and the rear of the controller.
- 3 Unscrew the 2 cross-head screws at the left side of the controller.
- 4 Remove top plate from the controller. Now you have access to the GEMAC interpolation board, see next figure.



- 5 Remove interpolation board. Below the interpolation board a DIP switch is located.
- 6 To use digital encoder input set all DIP switches to ON, see next figure.
Now the pinout of column "Without interpolation board" in the sensor pinout table below is valid.



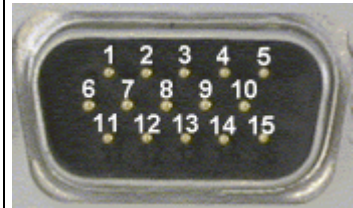
- 7 Attach top plate to controller by tightening the 2x2 cross-head screws to controller rear and front plates.
- 8 Connect sensor to sub-D sensor connector at rear of controller.
- 9 Reconnect the power supply to the E-861 to power it on.
- 10 Give an appropriate sensor reference signal to pin 1 of the sensor connector at the controller rear.
The reference signal is appropriate if it features:
 - TTL level
 - a minimum pulse length of more than 50 μ s, since 50 μ s is the controller servo loop time
- 11 Perform a sensor calibration as described in the sensor manufacturer's documentation.
Note that the reference pulse of the ruler, i.e. input signals to pin 3 and pin 8, cannot be used.
- 12 Check for proper function of the servo loop with the new sensor. To do so proceed as follows:
 - a) Open a connection using PIMikroMove, see steps 1 to 10 of "Getting Started" (p. 12) for instructions.
 - b) To send the commands as given below follow the *Tools* → *Command entry* menu sequence in the PIMikroMove main window, see figure below. Now you can send commands via the *Command entry* window.



- c) Activate servo by sending SVO 1 1
 - d) Send MOV 1 10
 - e) Send POS?
 - f) Compare response with commanded target position. If both values are consistent proceed with step 13. If they are not, repeat step 11.
- 13 If you are sure that the motion system works properly, shut down controller.

Pinout of Sensor Connector (15-pin sub-D connector)

Pin	With interpolation board	Without interpolation board
1	REF	REF
2	VDD (5 V output)	VDD (5 V output)
3	REFP (Positive reference trace from ruler)	cannot be used
4	COSP	B+
5	SINP	A+
6	PLIMIT	PLIMIT
7	NLIMIT	NLIMIT
8	Ref (negative reference trace from ruler)	cannot be used
9	COSN	B -
10	SINN	A -
11	internal use	internal use
12	VDD (5 V output)	VDD (5 V output)
13	GND	GND
14	GND	GND
15	GND	GND



9.5.3 GEMAC Parameters

The E-861 is equipped with a GEMAC interpolation board for incremental measuring systems.

The GEMAC parameters are set in the volatile or non-volatile memory of the controller, see "How to Store Parameter Settings" (p. 37) for instructions. Note that the parameters for the GEMAC board (IDs 0x7000010 to 0x7000011) are not part of a parameter set, i.e. stage database entry located on the host PC.

The parameters for the GEMAC board are preset for the following encoder hardware properties:

- Differential analog transmission of the sensor signals.
Note that the controller cannot process single-ended signals, even though the GEMAC board would allow it
- Sine and cosine signals have to be phase shifted by 90° relative to one another (obligatory)
- Sensor signal amplitude, i.e. of $\pm \sin$ and $\pm \cos$: 1.0 Vpp (obligatory)
- Offset for sensor signal, i.e. $\pm \sin$ and $\pm \cos$: 2.5 V (obligatory)

It is strongly recommended to use these parameter values, i.e. your sensor hardware properties must match the above-mentioned values, otherwise the GEMAC interpolation board may not work properly.

See the manual for the GEMAC interpolation board (IP1000_B_EN.pdf; provided on the E-861 CD) for information about interpolation details.

If you are sure that you wish to adjust GEMAC parameters proceed as follows:

- 1 Set the GEMAC parameters in volatile memory using SPA.
See "Parameter List" (p. 41) for assignment of E-861 parameters to the write registers of the GEMAC circuitry.

The following example shows how to configure the GEMAC CFG0 write register (e.g. interval time, interpolation rate) for axis 1:

Send SPA 1 0x7000010 252

See p. 16 of IP1000_EN.pdf for bit mapping of CFG0 write register. The setting is made in volatile memory only.

- 2 Test the functioning of the system.
- 3 If everything is okay and you want to use this system configuration after the next power-on, save the settings for the GEMAC

parameters from volatile to non-volatile memory.

For example:

Send WPA 4711

The password "4711" affects only the GEMAC parameters (for all other parameters, the password "100" is required). Since WPA is used without specifying any parameters, all currently valid GEMAC parameter values from volatile memory are saved, except for the write-protected parameters (see Note below).

NOTE

The GEMAC parameters cannot be changed with SEP. Use SPA and WPA to save their values to non-volatile memory.

The GEMAC parameters with the IDs 0x7000015, 0x7000016, 0x700001C, 0x700001D, 0x700001E and 0x700001F are write-protected and cannot be changed.

The E-861 will send no error message if you try to change those parameters.

9.5.4 Custom Sensor Using GEMAC Interpolation Board

If a custom sensor is to use the GEMAC interpolation board you have to provide the following items:

- Sensor delivering signals that match the requirements of the GEMAC interpolation board
See "GEMAC Parameters" (p. 105) for required sensor properties.
- Documentation of the sensor manufacturer for sensor calibration
- IP1000_B_EN.pdf, i.e. documentation of GEMAC interpolation board

In addition, the following condition has to be met:

- The servo loop input factor matches the custom sensor's resolution.
See "Servo Loop Input Factor" (p. 99) for details about this factor.
See "How to Store Parameter Settings" (p. 37) for instructions.

Details and preparation instructions for custom sensor calibration using the controller's interpolation board are given in the E861T0008 Technical Note. Call your PI representative or write to info@pi.ws to ask for this Technical Note if required.

10 GCS Commands

The PI General Command Set (GCS) is supported by a wide range of PI systems. This command set is well-suited for positioning tasks with one or more axes. The command set itself is independent of the specific hardware (controller or attached stages).

Commands are used to set operating modes, initiate axis motion and to query system and motion values. Because of the variety of functions and parameters, a sequence of commands must often be transferred in order to achieve a desired system action.

You can type commands, for example, in the *Command Terminal* or *Command Entry* windows, respectively, of NanoCapture and PIMikroMove, or in the PITerminal.

10.1 Format

10.1.1 Notation

The following notation is used to define the GCS syntax and to describe the commands:

<...>	Angle brackets indicate an argument of a command, can be an item identifier (p. 53) or a command-specific parameter
[...]	Square brackets indicate an optional entry
{...}	Braces indicate a repetition of entries, i.e. that it is possible to access more than one item (e.g. several axes) in one command line.
LF	LineFeed (ASCII char #10), is the default termination character
SP	Space (ASCII char #32)

10.1.2 GCS Syntax

Except as listed below, a GCS command consists of 3 characters, e.g. CMD. The corresponding query command has a "?" appended, e.g. CMD?. Command mnemonic:

CMD ::= character1 character2 character3 [?]

Exceptions:

- Special commands, e.g. fast polling commands, consist only of one character. The 24th ASCII character e.g. is called #24. Note that these commands are not followed by a termination character (but the responses to them are).
- *IDN? (for GPIB compatibility).

The command mnemonic is not case-sensitive.

General:

`CMD[{{SP}<argument>}}LF`

That means the command mnemonic and all arguments (e.g. axis IDs, channel IDs, parameters, etc.) must be separated from each other by one space.

Example:

Send: `MOVSP1SP10.0LF`

to move Axis 1 to position 10.0 (the unit depends on the controller, can be μm or mm, for example)

More than one command mnemonic per line is not allowed. Several groups of arguments following a command mnemonic are allowed, e.g.

`MOVSP1SP17.3SP2SP2.05LF`

if there were 2 axes. The command line ends with the termination character (LF).

If part of a command line cannot be executed, the line is not executed at all.

When all arguments are optional and are omitted, the command is executed for all possible argument values. For example,

`RPALF`

resets all parameters in volatile memory.

The `<AxisID>` argument is used for the logical axes of the controller. Depending on the controller, an axis could be identified with up to 16 characters—all alphanumeric characters and the underscore are allowed. See "Accessible Items and Their Identifiers" (p. 53) for the identifiers supported by the E-861.

Definitions for query commands (report commands):

`CMD?{{SP}<argument>}}LF`

When all arguments are optional and are omitted, all possible values are reported. For example,

`POS?`

queries the position of all axes.

Reply syntax:

```
[<argument>[{SP<argument>}]"]="<value>LF
```

Multi-line reply syntax:

```
{[<argument>[{SP<argument>}]"]="<value>SP LF}
[<argument>[{SP<argument>}]"]="<value>LF    for the last line!
```

The command

```
CMD?SP<arg3>SP <arg1>SP <arg2>LF
```

replies in the same order:

```
<arg3>"]="<value3>SP LF
<arg1>"]="<value1>SP LF
<arg2>"]="<value2> LF
```

Example:

```
Send:    TSP?SP2SP1
Report:  2=-1158.4405SP LF
         1=+0000.0000LF
```

NOTE

With the E-861, you can address only one single item (e.g. axis or channel) per command line, or, if the command supports this, address all items by omitting the item identifier.

Example:

You can send

```
SEP 100 1 0x32 0
```

to save a new value of parameter 0x32 for axis 1 to non-volatile memory

but it is not possible to send

```
SEP 100 1 0x32 0 1 0x14 1
```

10.1.3 Target and Sender Address

In principle, the addresses of the target controller and the sender are required in every command line, even with single-character commands like #4 or when recording a macro. But because only the host PC may send command lines to the E-861s, its address (0) can be omitted. Both target and sender address, however, are part of any controller response.

Example:

In a terminal, e.g. PITerminal, you can ask with the *IDN? command for the identification string of the E-861 with address 2 either by sending

2 0 *idn?

or by sending

2 *idn?

The response in either case is

0 2 (c)2010 Physik Instrumente(PI) Karlsruhe,E-861 Version 7.2.0

Exception:

The target address can be omitted if the target E-861 has the address 1, even if this E-861 is part of a daisy chain. If the target address is omitted, the target and sender addresses will also be omitted in any response of the controller.

Example:

If you send

*idn?

the controller with the address 1 will respond with

(c)2010 Physik Instrumente(PI) Karlsruhe,E-861 Version 7.2.0

If you send

1 *idn?

it will respond with

0 1 (c)2010 Physik Instrumente(PI) Karlsruhe,E-861 Version 7.2.0

See "DIP Switch Settings" for how to set the controller address. Possible controller addresses are in the range of 1 to 16, address 1 is default. The host PC always has the address 0. With the broadcast address 255, all controllers in a daisy chain can be addressed at the same time, but no reports are displayed on the host PC.

NOTES

In a daisy-chain, connected via USB or via RS-232, there must be one controller with address 1. It is not required that this controller is directly connected to the host PC, i.e. this controller does not have to be the first controller of the daisy-chain.

If there is no controller in a daisy-chain with address 1 an error message occurs when you try to setup a connection.

10.2 Command Survey

#4 (p. 114)	Request Status Register
#5 (p. 115)	Request Motion Status
#7 (p. 116)	Request Controller Ready Status
#8 (p. 116)	Query If Macro Is Running
#24 (p. 117)	Stop All Motion
*IDN? (p. 117)	Get Device Identification
ACC (p. 118)	Set Acceleration
ACC? (p. 118)	Get Acceleration
CST? (p. 119)	Get Stage Type Of Selected Axis
CSV? (p. 119)	Get Current Syntax Version
DEC (p. 119)	Set Deceleration
DEC? (p. 120)	Get Deceleration
DEL (p. 120)	Delay The Command Interpreter
DIO (p. 121)	Set Digital Output Lines
DIO? (p. 121)	Get Digital Input Lines
DRC (p. 122)	Set Data Recorder Configuration
DRC? (p. 123)	Get Data Recorder Configuration
DRR? (p. 124)	Get Recorded Data Values
DRT (p. 126)	Set Data Recorder Trigger Source
DRT? (p. 127)	Get Data Recorder Trigger Source
ERR? (p. 127)	Get Error Number
FED (p. 128)	Find Edge
FNL (p. 129)	Fast Move To Negative Limit

FPL (p. 131)	Fast Move To Positive Limit
FRF (p. 133)	Fast Move To Reference Switch
FRF? (p. 134)	Get Referencing Result
GOH (p. 135)	Go To Home Position
HDR? (p. 135)	Get All Data Recorder Options
HLP? (p. 136)	Get List of Available Commands
HLT (p. 137)	Halt Motion Smoothly
HPA? (p. 138)	Get List of Available Parameters
JAS? (p. 138)	Query Joystick Axis Status
JAX (p. 139)	Set Axis Controlled By Joystick
JAX? (p. 140)	Get Axis Controlled By Joystick
JBS? (p. 140)	Query Joystick Button Status
JDT (p. 141)	Set Joystick Default Lookup Table
JLT (p. 142)	Fill Joystick Lookup Table
JLT? (p. 143)	Get Joystick Lookup Table Values
JON (p. 145)	Set Joystick Activation Status
JON? (p. 145)	Get Joystick Activation Status
LIM? (p. 146)	Indicate Limit Switches
MAC (p. 146)	Call Macro Function
MAC? (p. 149)	List Macros
MEX (p. 149)	Stop Macro Execution Due To Condition
MOV (p. 151)	Set Target Position
MOV? (p. 152)	Get Target Position
MVR (p. 153)	Set Target Relative To Current Position
OAC (p. 154)	Set Open-Loop Acceleration

OAC? (p. 155)	Get Open-Loop Acceleration
OAD (p. 155)	Open-Loop Analog Driving
OAD? (p. 157)	Get Voltage For Open-Loop Analog Motion
ODC (p. 157)	Set Open-Loop Deceleration
ODC? (p. 158)	Get Open-Loop Deceleration
OMA (p. 158)	Absolute Open-Loop Motion
OMA? (p. 160)	Get Open-Loop Target Position
OMR (p. 161)	Relative Open-Loop Motion
ONT? (p. 163)	Get On Target State
OSM (p. 163)	Open-Loop Step Moving
OVL (p. 165)	Set Open-Loop Velocity
OVL? (p. 166)	Get Open-Loop Velocity
POS (p. 166)	Set Real Position
POS? (p. 167)	Get Real Position
RBT (p. 167)	Reboot System
RMC? (p. 168)	List Running Macros
RNP (p. 168)	Relax PiezoWalk Piezos
RON (p. 170)	Set Reference Mode
RON? (p. 170)	Get Reference Mode
RPA (p. 171)	Reset Volatile Memory Parameters
RTR (p. 171)	Set Record Table Rate
RTR? (p. 172)	Get Record Table Rate
SAI? (p. 172)	Get List Of Current Axis Identifiers
SEP (p. 173)	Set Nonvolatile Memory Parameters
SEP? (p. 174)	Get Nonvolatile Memory Parameters

SPA (p. 175)	Set Volatile Memory Parameters
SPA? (p. 178)	Get Volatile Memory Parameters
SRG? (p. 178)	Query Status Register Value
SSA (p. 180)	Set Step Amplitude
SSA? (p. 180)	Get Step Amplitude
STE (p. 181)	Start Step And Response - Measurement
STP (p. 182)	Stop All Motion
SVO (p. 183)	Set Servo State (Open-Loop / Closed-Loop Operation)
SVO? (p. 185)	Get Servo State (Open-Loop / Closed-Loop Operation)
TAC? (p. 185)	Tell Analog Channels
TAV? (p. 185)	Get Analog Input Voltage
TIO? (p. 186)	Tell Digital I/O Lines
TMN? (p. 186)	Get Minimum Commandable Position
TMX? (p. 187)	Get Maximum Commandable Position
TNR? (p. 187)	Get Number Of Record Tables
TRS? (p. 188)	Indicate Reference Switch
VEL (p. 188)	Set Closed-Loop Velocity
VEL? (p. 189)	Get Closed-Loop Velocity
WAC (p. 189)	Wait For Condition For Macro Execution
WPA (p. 190)	Save Parameters To Nonvolatile Memory

10.3 Command Reference (alphabetical)

#4 (Request Status Register)

Description: Requests system status information.

Format: #4 (single ASCII character number 4)

Arguments: none

Response: The answer is bit-mapped. See below for the individual codes.

Notes: This command is identical in function to SRG? (p. 178), but only one character must be send via the interface. Therefore #4 can also be used while the controller is performing time-consuming tasks.

Note that this command might deliver no response as long as the controller performs a motion with the PiezoWalk Driving mode parameter 0x7001A00 set to 1, i.e. if automatic alternating of motion modes is activated and being performed.

For the E-861, the response is the sum of the following codes, in hexadecimal format:

Bit	15	14	13	12	11	10	9	8
Description	On Target	Is referencing	Is moving	Servo On	Transitions between motion and servo modes: Analog = 0 Relaxing = 1 Go to analog = 2 Relaxed = 3 In motion = 4 Go to motion = 5 See "Modes of Operation" (p. 54) for details.			

Bit	7	6	5	4	3	2	1	0
Description	Digital Input 4	Digital Input 3	Digital Input 2	Digital Input 1	-	Positive Limit	Reference	Negative Limit

Example: Send: #4
 Receive: 0x9405
 Note: The response is given in hexadecimal format. It means that the axis is on target, the servo is on, the axis is ready for closed-loop motion (In motion state), the states of the digital input lines 1 to 4 are low, and the stage is on the positive side of the reference switch (limits are not active, note that the logic of the signals is inverted in this example)

#5 (Request Motion Status)

Description: Requests motion status of the axes.

Format: #5 (single ASCII character number 5)

Arguments: none

Response: The answer <uint> is bit-mapped and returned as the hexadecimal sum of the following codes:

1=first axis is moving
2=second axis is moving
4=third axis is moving

...

Examples: 0 indicates motion of all axes complete
3 indicates that the first and the second axis are moving

#7 (Request Controller Ready Status)

Description: Asks controller for ready status (tests if controller is ready to perform a new command).

Note: Use #5 (p. 115) instead of #7 to verify if motion has finished.

Format: #7 (single ASCII character number 7)

Arguments: none

Response: B1h (ASCII character 177 = "±" in Windows) if controller is ready

B0h (ASCII character 176 = "°" in Windows) if controller is not ready
(e.g. performing a referencing command)

Troubleshooting: The response characters may appear differently in non-Western character sets or other operating systems. They may be indistinguishable on the controller screen.

#8 (Query If Macro Is Running)

Description: Tests if a macro is running on the controller.

Format: #8 (single ASCII character number 8)

Arguments: none

Response: <uint>=0 no macro is running
<uint>=1 a macro is currently running

#24 (Stop All Axes)

Description: Stops all axes abruptly. For details see the notes below.

Sets error code to 10.

This command is identical in function to STP (p. 182), but only one character must be send via the interface. Therefore #24 can also be used while the controller is performing time-consuming tasks.

Format: #24 (ASCII character 24)

Arguments: none

Response: none

Notes: #24 stops all motion caused by move commands (MOV (p. 151), MVR (p. 153), OAD (p. 155), OSM (p. 163), OMA (p. 158), OMR (p. 161), STE (p. 181)), referencing commands (FNL (p. 129), FPL (p. 131), FRF (p. 133)) and macros (MAC (p. 146)).

After the axes are stopped, if servo is on, their target positions are set to their current positions.

HLT (p. 137) in contrast to STP stops motion with given system deceleration with regard to system inertia.

*IDN? (Get Device Identification)

Description: Reports the device identity number.

Format: *IDN?

Arguments: none

Response: One-line string terminated by line feed with controller name, serial number and firmware version

Notes: For E-861, *IDN? replies something like:

(c)2010 Physik Instrumente(PI) Karlsruhe,E-861
Version 7.2.0

ACC (Set Closed-Loop Acceleration)

Description: Set acceleration of given axes.

The ACC setting only takes effect when the given axis is in closed-loop operation (servo on).

ACC can be changed while the axis is moving.

Format: ACC {<AxisID> <Acceleration>}

Arguments: <AxisID> is one axis of the controller

<Acceleration> is the acceleration value in physical units/s².

Response: none

Troubleshooting: Illegal axis identifiers

Notes: The lowest possible value for <Acceleration> is 0.

ACC changes the value of the Current closed-loop acceleration parameter (ID 0xB) in volatile memory (can be saved as power-on default with WPA (p. 190), can also be changed with SPA (p. 175) and SEP (p. 173)).

The maximum value which can be set with the ACC command is given by the Maximum closed-loop acceleration parameter, ID 0x4A (can be changed with SPA (p. 175) and SEP (p. 173)).

ACC? (Get Closed-Loop Acceleration)

Description: Get the current value of the closed-loop acceleration.

If all arguments are omitted, gets current value of all axes.

Format: ACC? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the current active closed-loop acceleration value in physical units / s².

CST? (Get Assignment of Stages to Axes)

Description: Returns the name of the connected stage for the queried axis.

Format: CST? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<string> LF}

where

Notes: <string> is the name of the stage assigned to the axis. The stage name is read from the Stage Name parameter (ID 0x3C) whose factory default value is "DEFAULT_STAGE-N". You can set the parameter value to the name of your stage using SPA (p. 175) or SEP (p. 173). See also "Controller Parameters" (p. 35).

CSV? (Get Current Syntax Version)

Description: Get current GCS syntax version used in the firmware.

Format: CSV?

Arguments: none

Response: The current GCS syntax version, can be 1.0 (for GCS 1.0) or 2.0 (for GCS 2.0)

DEC (Set Closed-Loop Deceleration)

Description: Set deceleration of given axes.

The DEC setting only takes effect when the given axis is in closed-loop operation (servo on).

DEC can be changed while the axis is moving.

Format: DEC {<AxisID> <Deceleration>}

Arguments: <AxisID> is one axis of the controller

<Deceleration> is the deceleration value in physical units/s².

Response: none

Troubleshooting: Illegal axis identifiers

- Notes:** The lowest possible value for <Deceleration> is 0.
- DEC changes the value of the Current closed-loop deceleration parameter (ID 0xC) in volatile memory (can be saved as power-on default with WPA (p. 190), can also be changed with SPA (p. 175) and SEP (p. 173)).
- The maximum value which can be set with the DEC command is given by the Maximum closed-loop deceleration parameter, ID 0x4B (can be changed with SPA (p. 175) and SEP (p. 173)).

DEC? (Get Closed-Loop Deceleration)

Description: Get the current value of the closed-loop deceleration.

If all arguments are omitted, gets current value of all axes.

Format: DEC? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the current active closed-loop deceleration value in physical units / s².

DEL (Delay The Command Interpreter)

Description: Delays <uint> milliseconds.

Format: DEL <uint>

Arguments: <uint> is the delay value in milliseconds.

Response: none

Notes: See the MAC command (p. 146) and "Working with Controller Macros" (p. 82) for more information.

DIO (Set Digital Output Line)

Description: Switches the specified digital output line(s) to specified state(s).

Use TIO? (p. 186) to get the number of installed digital I/O lines.

Format: DIO {<DIOID> <OutputOn>}

Arguments: <DIOID> is one digital output line of the controller, see below for details

<OutputOn> is the state of the digital output line, see below for details

Response: none

Notes: Using the DIO command, you can activate/deactivate the Output 1 to Output 4 lines which are located on the "I/O" socket (p. 218). With the E-861, you can either set a single line per DIO command, or all lines at once.

The <DIOID> identifiers to use for the lines are 1 to 4. With the identifier 0, all lines are set according to a bit pattern given by <OutputOn>.

If <OutputOn>=1 the line is set to HIGH/ON, if <OutputOn>=0 it is set to LOW/OFF. If <DIOID> = 0, a bit pattern can be set in decimal or hexadecimal format which gives the states for all lines.

Do not use DIO on output lines for which the trigger output is activated with TRO.

DIO? (Get Digital Input Lines)

Description: Lists the states of the specified digital input lines. Can be used to query externally generated signals.

Use TIO? (p. 186) to get the number of installed digital I/O lines.

Format: DIO? [{<DIOID>}]

Arguments: <DIOID> is the identifier of the digital input line, see below for details

Response: {<DIOID>="<InputOn> LF}

where

<InputOn> gives the state of the digital input line, see below for details

Notes: Using the DIO? command, you can directly read the Input 1 to Input 4 lines which are located on the "I/O" socket (p. 218). With the E-861, you can either read a single line per DIO? command, or all lines at once.

The <DIOID> identifiers to use for the lines are 1 to 4. If the identifier is omitted or 0, all lines are queried.

If <InputOn>=0, the digital input is LOW/OFF, if <InputOn>=1, the digital input is HIGH/ON. If <DIOID> is 0, <InputOn> is a bit pattern which gives the states of all lines in hexadecimal format.

DRC (Set Data Recorder Configuration)

Description: Set data recorder configuration: determines the data source and the kind of data (RecordOption) used for the given data recorder table.

Format: DRC <RecTableID> <Source> <RecOption>

Arguments: <RecTableID>: is one data recorder table of the controller, see below

<Source>: is the data source, for example an axis, output signal channel or input signal channel of the controller. The required source depends on the selected record option.

<RecOption>: is the kind of data to be recorded (record option).

See below for a list of the available record options and the corresponding data sources.

Response: none

Notes: The E-861 has two data recorder tables with 1024 points per table.

With HDR? (p. 135) you will obtain a list of available record and trigger options and additional information about data recording. The number of available data recorder tables can be read with TNR? (p. 187).

For detailed information see "Data Recording" (p. 88).

Available record options with the appropriate data sources:

- 0=Nothing is recorded
- 1=Target Position of axis (i.e. target position in closed-loop operation)
- 2=Current Position of axis
- 3=Position Error of axis
- 70=Commanded Velocity of axis (open-loop or closed-loop velocity, depending on the current servo state)
- 71=Commanded Acceleration of axis (open-loop or closed-loop acceleration, depending on the current servo state)
- 73=Motor Output of axis
- 80=Signal Status Register of axis
- 81=Analog Input of input channel

Note: The input channels can be the Input 1 to 4 lines of the I/O socket (p. 218) (use source ID 1 to 4) and the joystick axis (source ID 5) and joystick button inputs (source ID 6) on the Joystick socket (p. 220). The source ID 7 is reserved for an additional analog input channel.

DRC? (get Data Recorder Configuration)

Description: Returns settings made with DRC (p. 122).

Format: DRC? [{<RecTableID>}]

Arguments: <RecTableID>: is one data recorder table of the controller; if omitted settings for all tables are given.

Response: The current DRC settings:

```
{<RecTableID>=" "<Source> <RecOption> LF}
```

where

<Source>: is the data source, for example an axis or an output signal channel of the controller. The source type depends on the record option.

<RecOption>: is the kind of data to be recorded

See DRC for a list of the available record options and the corresponding data sources.

DRR? (Get Recorded Data Values)

Description: Reading of the last recorded Data Set.

Reading can take some time depending on the number of points to be read!

It is possible to read the data while recording is still in progress.

Format: DRR? [<StartPoint> <NumberOfPoints> [{<RecTableID>}]]

Arguments: <StartPoint>: is the first point to be read from the data recorder table, starts with index 1

<NumberOfPoints>: is the number of points to be read per table

<RecTableID>: is one data recorder table of the controller

Response: The recorded data in GCS array format, see the separate manual for GCS array, SM 146E, and the example below

Notes: If <DataRecorderTable> is omitted, the data from all tables with non-zero record option (see DRC (p. 122)) is read.

With HDR? (p. 135) you will obtain a list of available record options and trigger options and additional information about data recording.

For detailed information see "Data Recording" (p. 88).

Example:

```
dr? 1 20
# REM E-861
#
# VERSION = 1
# TYPE = 1
# SEPARATOR = 32
# DIM = 2
# SAMPLE_TIME = 0.000020
# NDATA = 20
#
# NAME0 = Actual Position of Axis AXIS:1
# NAME1 = Position Error of Axis AXIS:1
#
# END_HEADER
5.00000 0.00000
4.99998 0.00002
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
4.99998 0.00002
5.00000 0.00000
4.99998 0.00002
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
5.00000 0.00000
4.99998 0.00002
5.00000 0.00000
4.99998 0.00002
4.99998 0.00002
5.00000 0.00002
4.99998 0.00004
```

DRT (Set Data Recorder Trigger Source)

Description: Defines a trigger source for the given data recorder table.

Format: DRT <RecTableID> <TriggerSource> <Value>

Arguments: <RecTableID> is one data recorder table of the controller. See below for details.

<TriggerSource> ID of the trigger source, see below for a list of available options

<Value> depends on the trigger source, can be a dummy, see below

Response: none

Notes: By default data recording is triggered when a step response measurement is made with STE (p. 181).

A trigger option set with DRT will become valid for all data recorder tables with non-zero record option (see DRC (p. 122)).

With HDR? (p. 135) you will obtain a list of available record options and trigger options and additional information about data recording.

For detailed information see "Data Recording" (p. 88).

Available trigger options:

- 0 = default setting; data recording is triggered with STE; <Value> must be a dummy
- 1 = any command changing position (e.g. MVR (p. 153), MOV (p. 151), OAD (p. 155), OSM (p. 163)); <Value> must be a dummy
- 2 = next command, resets trigger after execution; <Value> must be a dummy
- 3 = reserved
- 4 = reserved
- 5 = reserved
- 6 = any command changing position (e.g. MVR, MOV, OAD, OSM), resets trigger after execution; <Value> must be a dummy

DRT? (Get Data Recorder Trigger Source)

Description: Returns the trigger source for the data recorder tables.

Format: DRT? [{<RecTableID>}]

Arguments: <RecTableID> is one data recorder table of the controller

Response: {<RecTableID>="<TriggerSource> <Value> LF}

where

<TriggerSource> is the ID of the trigger source, see DRT (p. 126) for details

<Value> depends on the trigger source, if 0 it is a dummy, see DRT for details

Notes: Since all data recorder tables of the E-861 have the same trigger source, the DRT? response is given as a single line of the form

0=<TriggerSource> <Value>

ERR? (Get Error Number)

Description: Get error code <int> of the last occurred error and reset the error to 0.

Only the last error is buffered. Therefore you should call ERR? after each command.

The error codes and their descriptions are fully listed in "Error Codes" (p. 192).

Format: ERR?

Arguments: none

Response: The error code of the last occurred error (int).

Troubleshooting: Communication breakdown

FED (Find Edge)

Description: Moves given axis to a given signal edge.

In contrast to the referencing commands (FNL (p. 129), FPL (p. 131) and FRF (p. 133)), this command does not change the reference state of the axis and does not set a certain position value at the selected edge. It does move out of the limit condition, therefore the axis motion finishes at the same position as with the corresponding referencing commands.

If multiple axes are given in the command, they are moved synchronously.

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: FED {<AxisID> <EdgeID> <Param>}

Arguments: <AxisID> is one axis of the controller.

<EdgeID> is the type of edge the axis has to move to. See below for available edge types.

<Param> depends on the selected edge and qualifies it. See below for details.

Response: none

Troubleshooting: Illegal axis identifier; limit switches and/or reference switch are disabled (see below); servo is off

Notes: This command can be used both with servo enabled or disabled (open-loop and closed-loop operation) for the commanded axis, see SVO (p. 183) command description .

The E-861 firmware detects the presence or absence of reference switch and limit switches using controller parameters (ID 0x14 for reference switch; ID 0x32 for limit switches).

According to the values of those parameters, the E-861 enables or disables FED motions to the appropriate signal edges.

Adapt the parameter values to your hardware using

SPA (p. 175) or SEP (p. 173). See "Controller Parameters" (p. 35) for more information. FED can be used to measure the physical travel range of a new mechanics and thus to identify the values for the corresponding controller parameters: the distance from negative to positive limit switch, the distance between the negative limit switch and the reference switch (DISTANCE_REF_TO_N_LIM, parameter ID 0x17), and the distance between reference switch and positive limit switch (DISTANCE_REF_TO_P_LIM, parameter ID 0x2F). See "Travel Range Adjustment" (p. 92) for more information.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Motion commands like FED are not allowed when the joystick is active for the axis. See "Joystick Control" (p. 79) for details.

Available edge types and parameters:

The following edge types with their parameter settings are available:

1 = negative limit switch, <Param> must be 0

2 = positive limit switch, <Param> must be 0

3 = reference switch, <Param> must be 0

FNL (Fast Reference Move To Negative Limit)

Description: Performs a reference move.

Moves the given axis to the negative physical limit of its travel range and sets the current position to a defined value. See below for details.

If multiple axes are given in the command, they are moved synchronously.

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format:	FNL [{<AxisID>}]
Arguments:	<AxisID> is one axis of the controller, if omitted, all axes are affected.
Response:	none
Troubleshooting:	Illegal axis identifier
Notes:	<p>This command can be used both with servo enabled or disabled for the commanded axis, see SVO (p. 183) command description.</p> <p>If reference move was successful, absolute motion will afterwards be possible in open-loop and in closed-loop operation.</p> <p>The reference mode must be set to "1" (factory default) with the RON command (p. 170) if referencing is to be done by performing a reference move. See "Referencing" (p. 51) for further details.</p> <p>With the E-861, the negative limit switch of the mechanics is used to determine the negative physical limit of the travel range. The difference of VALUE_AT_REF_POS (parameter ID 0x16) and DISTANCE_REF_TO_N_LIM (parameter ID 0x17) is set as the current position when the axis is at the negative limit switch (value can be negative).</p> <p>This command can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).</p> <p>Use FRF? (p. 134) to check whether the reference move was successful.</p> <p>Use FRF (p. 133) instead of FNL to perform a reference move for an axis which has no limit switches but a reference sensor.</p> <p>For best repeatability, always reference in the same way.</p> <p>If the soft limits (MAX_TRAVEL_RANGE_POS and MAX_TRAVEL_RANGE_NEG) are used to reduce the travel range, the limit switches cannot be used for reference moves. The FNL and FPL commands will provoke an error message, and only the reference switch can be used for a reference move (FRF).</p> <p>The soft limits may not be outside of the physical travel range:</p>

$$\begin{aligned} \text{MAX_TRAVEL_RANGE_POS} &\leq \\ &\text{DISTANCE_REF_TO_P_LIM} + \\ &\text{VALUE_AT_REF_POS} \\ \text{MAX_TRAVEL_RANGE_NEG} &\geq \\ &\text{VALUE_AT_REF_POS} - \\ &\text{DISTANCE_REF_TO_N_LIM} \end{aligned}$$

Otherwise, reference moves to the limit switches would have incorrect results because the values of the soft limits would be set at the end of the referencing procedure.

See "Travel Range Adjustment" (p. 92) for more information.

FPL (Fast Reference Move To Positive Limit)

Description: Performs a reference move.

Moves the given axis to the positive physical limit of its travel range and sets the current position to a defined value. See below for details.

If multiple axes are given in the command, they are moved synchronously.

Caution: Do not use this command if no sensor is present in your system.

Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: FPL [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller, if omitted, all axes are affected.

Response: none

Troubleshooting: Illegal axis identifier

Notes: This command can be used both with servo enabled or disabled for the commanded axis, see SVO (p. 183) command description.
If reference move was successful, absolute motion will afterwards be possible in open-loop and in closed-loop operation.

The reference mode must be set to "1" (factory default) with the RON command (p. 170) if

referencing is to be done by performing a reference move. See "Referencing" (p. 51) for further details.

With the E-861, the positive limit switch of the mechanics is used to determine the positive physical limit of the travel range. The sum of VALUE_AT_REF_POS (parameter ID 0x16) and DISTANCE_REF_TO_P_LIM (parameter ID 0x2F) is set as the current position when the axis is at the positive limit switch.

This command can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Use FRF? (p. 134) to check whether the reference move was successful.

Use FRF (p. 133) instead of FPL to perform a reference move for an axis which has no limit switches but a reference sensor.

For best repeatability, always reference in the same way.

If the soft limits (MAX_TRAVEL_RANGE_POS and MAX_TRAVEL_RANGE_NEG) are used to reduce the travel range, the limit switches cannot be used for reference moves. The FNL and FPL commands will provoke an error message, and only the reference switch can be used for a reference move (FRF).

The soft limits may not be outside of the physical travel range:

$$\text{MAX_TRAVEL_RANGE_POS} \leq \text{DISTANCE_REF_TO_P_LIM} + \text{VALUE_AT_REF_POS}$$

$$\text{MAX_TRAVEL_RANGE_NEG} \geq \text{VALUE_AT_REF_POS} - \text{DISTANCE_REF_TO_N_LIM}$$

Otherwise, reference moves to the limit switches would have incorrect results because the values of the soft limits would be set at the end of the referencing procedure.

See "Travel Range Adjustment" (p. 92) for more information.

FRF (Fast Reference Move To Reference Switch)

Description: Performs a reference move.

Moves the given axis to the reference switch and sets the current position to a defined value. See below for details.

If multiple axes are given in the command, they are moved synchronously.

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: FRF [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller, if omitted, all axes are affected.

Response: none

Troubleshooting: Illegal axis identifier

Notes: This command can be used both with servo enabled or disabled for the commanded axis, see SVO (p. 183) command description.
If reference move was successful, absolute motion will afterwards be possible in open-loop and in closed-loop operation.

The reference mode must be set to "1" (factory default) with the RON command (p. 170) if referencing is to be done by performing a reference move. See "Referencing" (p. 51) for further details.

The value of the VALUE_AT_REF_POS parameter (ID 0x16) is set as the current position when the axis is at the reference switch.

This command can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Use FRF? (p. 134) to check whether the reference move was successful.

Use FNL (p. 129) or FPL (p. 131) instead of FRF to

perform a reference move for an axis which has no reference sensor but limit switches.

For best repeatability, always reference in the same way. The FRF command always approaches the reference switch from the same side, no matter where the axis is when it is issued.

See "Travel Range Adjustment" (p. 92) for more information.

FRF? (Get Referencing Result)

Description: Indicates whether the given axis is referenced or not.

An axis is considered as "referenced" when the current position value is set to a known position. This is the case when a reference move was successfully performed with FNL (p. 129), FPL (p. 131) or FRF (p. 133) or when the position was set directly with POS (p. 166) (depending on the referencing mode set with RON (p. 170)).

Format: FRF? [{<AxisID>}]

Arguments: <AxisID>: is one axis of the controller

Response: {<AxisID>="<uint> LF}

where

<uint> indicates whether the axis was successfully referenced (=1) or not (=0).

Troubleshooting: Illegal axis identifier

GOH (Go To Home Position)

Description: Move given axes to home position.

GOH [{<AxisID>}]
is the same as
MOV [{<AxisID> 0}]

Servo must be enabled for the commanded axis prior to using this command (closed-loop operation).

This command can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: GOH [{<AxisID>}]

Arguments: <AxisID>: is one axis of the controller, if omitted, all axes are affected

Response: none

Troubleshooting: Illegal axis identifier

HDR? (Get All Data Recorder Options)

Description: List a help string which contains all information available about data recording (record options and trigger options, information about additional parameters and commands concerned with data recording).

Format: HDR?

Arguments: none

Response: #RecordOptions
 {<RecordOption>="<DescriptionString>[of
 <Channel>]}

#TriggerOptions
 [{<TriggerOption>="<DescriptionString>}]

#Parameters to be set with SPA
 [{<ParameterID>="<DescriptionString>}]

#Additional information
 [{<Command description>("<Command>")}]

end of help

Example: For the E-861, the HDR? response is as follows:

```
#RecordOptions
0=Nothing is recorded
1=Commanded Position of Axis
2=Actual Position of Axis
3=Position Error of Axis
70=Commanded Velocity of Axis
71=Commanded Acceleration of Axis
73=Motor Output of Axis
80=Signal Status Register of Axis
81=Analog input (Channel = 1 to 7)
#TriggerOptions
0=default setting
1=any command changing position (e.g. MOV)
2=next command
6=any command changing position (e.g. MOV), reset
trigger after execution
#Additional information
2 record tables
1024 datapoints per table
end of help
```

Note: TriggerOptions = 0 (default) means that recording is triggered by the STE (p. 181) command.

HLP? (Get List Of Available Commands)

Description: List a help string which contains all commands available.

Format: HLP?

Arguments: none

Response: List of commands available

Troubleshooting: Communication breakdown

HLT (Halt Motion Smoothly)

Description: Halt the motion of given axes smoothly. For details see the notes below.

Error code 10 is set.

#24 (p. 117) and STP (p. 182) in contrast abort current motion as fast as possible for the controller without taking care of systems inertia or oscillations.

Format: HLT [{<AxisID>}]

Arguments: <AxisID>: is one axis of the controller, if omitted all axes are halted

Response: none

Troubleshooting: Illegal axis identifier

Notes: HLT stops motion with given system deceleration with regard to system inertia.

HLT stops all motion caused by move commands (MOV (p. 151), MVR (p. 153), OAD (p. 155), OMA (p. 158), OMR (p. 161), OSM (p. 163), STE (p. 181)), referencing commands (FNL (p. 129), FPL (p. 131), FRF (p. 133)) and macros (MAC (p. 146)).

After the axes are stopped, if servo is on their target positions are set to their current positions.

HPA? (Get List Of Available Parameters)

Description: Responds with a help string which contains all available parameters with short descriptions. See "Controller Parameters" (p. 35) for further details.

The listed parameters can be changed and/or saved using the following commands:

SPA (p. 175) affects the parameter settings in volatile memory (RAM).

WPA (p. 190) copies parameter settings from RAM to non-volatile memory.

SEP (p. 173) writes parameter settings directly into non-volatile memory (without changing RAM settings).

RPA (p. 171) resets RAM to the values from non-volatile memory.

Format: HPA?

Arguments: none

Response: {<PamID>="<string> LF}

where

<PamID> is the ID of one parameter, hexadecimal format

<string> is a string which describes the corresponding parameter.

The string has following format:

<ParameterDescription> is the parameter name

JAS? (Query Joystick Axis Status)

Description: Get the current status of the given axis of the given joystick device which is directly connected to the controller.

Format: JAS? [{<JoystickID> <JoystickAxis>}]

Arguments:	<p><JoystickID> is one joystick device connected to the controller; see below for details</p> <p><JoystickAxis> is one of the axes of the joystick device; see below for details</p>
Response:	<p>{<JoystickID> <JoystickAxis> "=" <Amplitude>}</p> <p>where</p> <p><Amplitude> is the factor which is currently applied to the current valid velocity setting of the controlled motion axis, corresponds to the current displacement of the joystick axis. See below for details.</p>
Notes:	<p>One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one axis of the joystick device, the identifier of the joystick axis is 1. See also "Accessible Items and Their Identifiers" (p. 53).</p> <p>The <Amplitude> factor is applied to the velocity set with VEL (p. 188) (closed-loop operation) or OVL (p. 165) (open-loop operation), the range is -1.0 to 1.0. Examples: With a factor of 0, the joystick axis is at the center position; with a factor of -0.7, the displacement of the joystick axis is about 2/3 in negative direction, provided that a linear lookup table is currently valid (see JLT (p. 142) for an example).</p>
JAX (Set Axis Controlled By Joystick)	
Description:	<p>Set axis controlled by a joystick which is directly connected to the controller.</p> <p>Each axis of the controller can only be controlled by one joystick axis.</p>
Format:	JAX <JoystickID> <JoystickAxis> <AxisID>
Arguments:	<p><JoystickID> is one joystick device connected to the controller; see below for details</p> <p><JoystickAxis> is one of the axes of the joystick device; see below for details</p> <p><AxisID> is one axis of the controller</p>
Response:	none

Notes: One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one axis of the joystick device, the identifier of the joystick axis is 1. See also "Accessible Items and Their Identifiers" (p. 53).

JAX? (Get Axis Controlled By Joystick)

Description: Get axis controlled by a joystick which is directly connected to the controller.

Format: JAX? [{<JoystickID> <JoystickAxis>}]

Arguments: <JoystickID> is one joystick device connected to the controller; see below for details

<JoystickAxis> is one of the axes of the joystick device; see below for details

Response: {<JoystickID> <JoystickAxis>="}{<AxisID> }LF}

where

<AxisID> is one axis of the controller

Notes: One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one axis of the joystick device, the identifier of the joystick axis is 1. See also "Accessible Items and Their Identifiers" (p. 53).

JBS? (Query Joystick Button Status)

Description: Get the current status of the given button of the given joystick device which is directly connected to the controller.

Format: JBS? [{<JoystickID> <JoystickButton>}]

Arguments: <JoystickID> is one joystick device connected to the controller; see below for details

<JoystickButton> is one of the buttons of the joystick device; see below for details

Response: {<JoystickID> <JoystickButton> "="<State>}

where

<State> indicates if the joystick button is pressed; 0 = not pressed, 1 = pressed

Notes: One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one button of the joystick device, the identifier of the joystick button is 1. See also "Accessible Items and Their Identifiers" (p. 53).

JDT (Set Joystick Default Lookup Table)

Description: Set lookup table type for the given axis of the given joystick device which is directly connected to the controller.

The current valid lookup-table content for the specified joystick axis is overwritten by the selection made with JDT.

Format: JDT {<JoystickID> <JoystickAxis> <uint>}

Arguments: <JoystickID> is one joystick device connected to the controller; see below for details

<JoystickAxis> is one of the axes of the joystick device; see below for details

<uint> defines the type of lookup-table profile to use; see below for details

Response: none

Notes: One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one axis of the joystick device, the identifier of the joystick axis is 1. See also "Accessible Items and Their Identifiers" (p. 53).

Available lookup tables: The E-861 provides the following types for the lookup-table profile:

1 = linear (power-on default)
2 = parabolic

JLT (Fill Joystick Lookup Table)

Description: Fill the lookup table for the given axis of the given joystick device which is directly connected to the controller.

The amplitudes of the joystick axes (i.e. their displacements) are mapped to the current valid velocity settings of the controller axes. For each joystick axis there is a lookup table that defines this mapping. With JLT this table can be written, or a default table profile provided by the controller can be loaded with the JDT command (p. 141).

Format: JLT <JoystickID> <JoystickAxis> <Addr> <floatn>

Arguments: <JoystickID> is one joystick device connected to the controller; see below for details

<JoystickAxis> is one of the axes of the joystick device; see below for details

<Addr> is the index of a point in the lookup table, starts with 1

<floatn> is the value of point n; 256 values must be written. The first point corresponds to the maximum joystick axis displacement in negative direction, the 256th point to the maximum displacement in positive direction.

Response: none

Notes: One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. The E-861 supports one axis of the joystick device, the identifier of the joystick axis is 1. See also "Accessible Items and Their Identifiers" (p. 53).

The <floatn> values are factors which will during joystick control be applied to the velocity set with VEL (p. 188) (closed-loop operation) or OVL (p. 165) (open-loop operation), the range is -1.0 to 1.0.

Notes:	<p>Example:</p> <p>In the current lookup table, point 1 has the value 1, hence the controlled axis will move with full velocity in positive direction at the maximum positive displacement of the joystick.</p> <p>Points 122 to 135 have the value 0, i.e. at the center position of the joystick and in a small area around the center, the velocity is 0 and the controlled axis will not move.</p> <p>Point 236 has the value -0.7021, i.e. when the displacement of the joystick axis is about 2/3 in negative direction, the controlled axis will move in negative direction with about 2/3 of the velocity.</p> <p>Point 256 has the value -1, i.e. the controlled axis will move with full velocity in negative direction at the maximum negative displacement of the joystick.</p>
JLT? (Get Joystick Lookup Table Values)	
Description:	Reading of the current valid lookup table values.
Format:	JLT? [<StartPoint> <NumberOfPoints> [{<JoystickID> <JoystickAxis>}]]
Arguments:	<p><StartPoint>: is the start point in the lookup table, starts with 1</p> <p><NumberOfPoints>: is the number of points to be read per joystick axis; maximum number is 256</p> <p><JoystickID> is one joystick device connected to the controller; see below for details</p> <p><JoystickAxis> is one of the axes of the joystick device; see below for details</p>
Response:	The lookup table content in GCS array format, see the separate manual for GCS array, SM 146E, and the example below

Notes: With the E-861, <JoystickID> and <JoystickAxis> must be omitted in the JLT? command, while <StartPoint> and <NumberOfPoints> are always required.

The <floatn> values in the lookup table are factors which will during joystick control be applied to the velocity set with VEL (p. 188) (closed-loop operation) or OVL (p. 165) (open-loop operation), the range is -1.0 to 1.0.

Example:

```
jlt? 1 20
# TYPE = 1
#
# SEPARATOR = 32
# DIM = 0
# NDATA = 20
# NAME0 = Joysticktable 1
# END HEADER
1.0000
0.9833
0.9677
0.9521
0.9365
0.9208
0.9052
0.8896
0.8750
0.8593
0.8447
0.8300
0.8154
0.8007
0.7861
0.7714
0.7578
0.7431
0.7294
0.7158
```

JON (Set Joystick Activation Status)

Description:	Enable or disable a joystick device which is directly connected to the controller. For joystick control of a controller axis, this axis must be assigned to a joystick axis with JAX (p. 139), and the corresponding joystick device must be enabled with JON.
Format:	JON {<JoystickID> <uint>}
Arguments:	<JoystickID> is one joystick device connected to the controller; see below for details <uint> 1 enables the joystick device, 0 disables joystick device
Response:	none
Notes:	One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. See also "Accessible Items and Their Identifiers" (p. 53). Motion commands like MOV (p. 151) or OSM (p. 163) are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

JON? (Get Joystick Activation Status)

Description:	Get activation state of the given joystick device which is directly connected to the controller.
Format:	JON? [{<JoystickID>}]
Arguments:	<JoystickID> is one joystick device connected to the controller; see below for details
Response:	{<JoystickID>="<uint>}" where <uint> is the joystick activation state: 1 = joystick device enabled, 0 = joystick device disabled
Notes:	One joystick device can be connected to the Joystick socket (p. 220) of the E-861, the identifier is 1. See also "Accessible Items and Their Identifiers" (p. 53).

LIM? (Indicate Limit Switches)

Description: Indicates whether axes have limit switches.

Format: LIM? [{<AxisID>}]

Arguments: <AxisID>: is one axis of the controller

Response: {<AxisID>="<uint> LF}

where

<uint> indicates whether the axis has limit switches
(=1) or not (=0).

Troubleshooting: Illegal axis identifier

Notes: The E-861 firmware detects the presence or absence of limit switches using a controller parameter (ID 0x32). According to the value of this parameter, the E-861 enables or disables the stopping of the motion at the limit switches and reference moves using FNL (p. 129) or FPL (p. 131). Adapt the parameter value to your hardware using SPA (p. 175) or SEP (p. 173). See "Controller Parameters" (p. 35) for more information.

MAC (Call Macro Function)

Description: Call a macro function. Permits recording, deleting and running macros on the controller.

Format: MAC <keyword> {<parameter>}

in particular:

MAC BEG <macroname>

MAC DEF <macroname>

MAC DEF?

MAC DEL <macroname>

MAC END

MAC NSTART <macroname> <uint>

MAC START <macroname>

Arguments:	<p><keyword> determines which macro function is called. The following keywords and parameters are used:</p> <p>MAC BEG <macroname> Start recording a macro to be named <i>macroname</i> on the controller; may not be used in a macro; the commands that follow become the macro, so if successful, the error code cannot be queried. End the recording with MAC END.</p> <p>MAC END Stop macro recording (cannot become part of a macro)</p> <p>MAC DEF <macroname> Set specified macro as start-up macro. This macro will be automatically executed with the next power-on or reboot of the controller. If <macroname> is omitted, the current start-up macro selection is canceled.</p> <p>MAC DEF? Ask for the start-up macro Response: <macroname> If no start-up macro is defined, the response is an empty string with the terminating character.</p> <p>MAC DEL <macroname> Deletes specified macro.</p> <p>: MAC NSTART <macroname> <uint> Repeat the specified macro <uint> times. Another execution is started when the last one is finished.</p> <p>MAC START <macroname> Starts one execution of specified macro.</p> <p>Response: none</p> <p>Troubleshooting: Macro recording is active (keywords BEG, DEL) or inactive (END) Macro contains a disallowed MAC command</p>
------------	--

Notes:

During macro recording no macro execution is allowed.

When a macro is recorded for a controller whose address is different from 1, the target ID must be part of each command line, but will not become part of the macro content. See "Defining Macros" (p. 82) and "Target and Sender Address" (p. 110) for more information.

A macro can be overwritten by a macro with the same name.

A running macro sends no responses to any interface. This means questioning commands are allowed in macros but not answered and therefore useless.

The following commands provided by the E-861 can only be used in macros:
DEL (p. 120), MEX (p. 149) and WAC (p. 189).

A macro can start another macro. Further nesting is not allowed (only one nesting level). A macro can call itself to form an infinite loop.

Any commands can be sent from the command line when a macro is running. The macro content and move commands received from the command line may overwrite each other, and only the last move command will be executed, irrespective of its source.

Macro execution can be stopped with #24 (p. 117), STP (p. 182) and HLT (p. 137).

Simultaneous execution of multiple macros is not possible. Only one macro can be executed at a time.

A running macro may not be deleted.

Macro execution is not allowed when a joystick is active on the axis, but macro recording is possible. See "Joystick Control" (p. 79) for details.

You can query with #8 (p. 116) if a macro is currently running on the controller.

Warning: The number of write cycles of non-volatile memory is limited.

MAC? (List Macros)

Description: List macros or content of a given macro.

Format: MAC? [<macroname>]

Arguments <macroname>: name of the macro whose content shall be listed; if omitted, the names of all stored macros are listed.

Response: <string>
if <macroname> was given, <string> is the content of this macro;
if <macroname> was omitted, <string> is a list with the names of all stored macros

Troubleshooting: Macro <macroname> not found

MEX (Stop Macro Execution Due To Condition)

Description: Stop macro execution due to a given condition of the following type: a specified value is compared with a queried value according to a specified rule.

Can only be used in macros.

When the macro interpreter accesses this command the condition is checked. If it is true the current macro is stopped, otherwise macro execution is continued with the next line. Should the condition be fulfilled later, the interpreter will ignore it.
See also WAC (p. 189).

Format: MEX <CMD?> <OP> <value>

Arguments <CMD?> is one questioning command in its usual syntax. The answer must consist of a single value. For an example see below.

<OP> is the operator to be used. The following operators are possible:
= <= < > >= !=

<value> is the value to be compared with the response of <CMD?>

Response: none

Example: Send: MAC START AMC001

Note: Macro "AMC001" has the following contents:

```
MAC START AMC002  
MAC START AMC003  
MEX DIO? 4 = 1  
MAC START AMC001
```

Macro "AMC002" has the following contents:

```
MEX DIO? 4 = 1  
MEX DIO? 1 = 0  
MVR 1 1.0  
DEL 100
```

Macro "AMC003" has the following content:

```
MEX DIO? 4 = 1  
MEX DIO? 2 = 0  
MVR 1 -1.0  
DEL 100
```

Macro AMC001 forms an infinite loop by permanently calling AMC002, AMC003 and itself.

AMC002 checks the state of the digital input channel 1 (located on the I/O socket (p. 218)). If it is not set (0), the macro is aborted, otherwise the macro will move axis 1 by 1.0 in positive direction (relative move).

AMC003 checks the state of the digital input channel 2 and moves axis 1 in negative direction accordingly.

Connecting the digital input channels 1, 2 and 4 with pushbuttons, e.g. with the C-170.PB pushbutton box, it is possible to implement interactive control of an axis without any software assistance. The delay (DEL 100) is required to avoid generation of multiple MVR commands while pressing the pushbutton for a short time.

Channel 4 is used as a global exit. Since MEX stops execution of the current macro only, it must also be included in the calling macro, which would otherwise continue.

MOV (Set Target Position)

Description: Set new absolute target position for given axis.

Servo must be enabled for the commanded axis prior to using this command (closed-loop operation).

Format: MOV {<AxisID> <Position>}

Arguments: <AxisID> is one axis of the controller

<Position> is the new absolute target position in physical units.

Response: none

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Notes: The target position must be inside the travel range limits. Use TMN? (p. 186) and TMX? (p. 187) to ask for the current valid travel range limits.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

During a move, a new move command resets the target to a new value and the old one may never be reached.

This is also valid with macros: move commands can be sent from the command line when a macro is running.

The macro content and move commands received from the command line may overwrite each other, and only the last move command will be executed, irrespective of its source.

Motion commands like MOV are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

Example 1: Send: MOV 1 10

Note: Axis 1 moves to 10 (target position in mm)

Example 2: Send: MOV 1 243
 Send: ERR?
 Receive: 7
 Note: The axis does not move. The error code "7" in the reply to the ERR? command (p. 127) indicates that the target position given in the move command is out of limits.

MOV? (Get Target Position)

Description: Returns last valid commanded target position.

Format: MOV? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the last commanded target position in physical units

Troubleshooting: Illegal axis identifier

Notes: The target position can be changed by commands that cause motion (e.g. MOV (p. 151), MVR (p. 153), GOH (p. 135), STE (p. 181)) or by the joystick (when disabling a joystick, the target position is set to the current position for joystick-controlled axes which are in closed-loop operation).

MOV? gets the commanded positions. Use POS? (p. 167) to get the current positions.
Note that if servo is disabled, MOV? does not deliver the last commanded position, but 0.

MVR (Set Target Relative To Current Position)

Description: Move given axes relative to the last commanded target position.

The new target position is calculated by adding the given value <Distance> to the last commanded target value.

Format: Servo must be enabled for the commanded axis prior to using this command (closed-loop operation).
MVR {<AxisID> <Distance>}

Arguments: <AxisID> is one axis of the controller.

<Distance> gives the distance to move; the sum of the distance and the last commanded target position is set as new target position (in physical units).

Response: none

Notes: Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

The target position must be inside the travel range limits. Use TMN? (p. 186) and TMX? (p. 187) to ask for the current valid travel range limits, and MOV? (p. 152) for the current target.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

During a move, a new move command resets the target to a new value and the old one may never be reached. This is also valid with macros: move commands can be sent from the command line when a macro is running. The macro content and move commands received from the command line may overwrite each other, and only the last move command will be executed, irrespective of its source.

Motion commands like MVR are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

Example:

```

Send:      MOV 1 0.5
Note:      This is an absolute move.
Send:      POS? 1
Receive:    1=0.500000
Send:      MOV? 1
Receive:    1=0.500000
Send:      MVR 1 2
Note:      This is a relative move.
Send:      POS? 1
Receive:    1=2.500000
Send:      MVR 1 2000
Note:      New target position of axis 1 would
            exceed motion range. Command is ignored, i.e. the
            target position remains unchanged, and the axis does
            not move.
Send:      MOV? 1
Receive:    1=2.500000
Send:      POS? 1
Receive:    1=2.500000

```

OAC (Set Open-Loop Acceleration)

Description: Set open-loop acceleration of given axes.

The OAC setting only takes effect when the given axis is in open-loop operation (servo off).

OAC can be changed while the axis is moving.

Format: OAC {<AxisID> <Acceleration>}

Arguments: <AxisID> is one axis of the controller

<Acceleration> is the acceleration value in step cycles/s².

Response: none

Troubleshooting: Illegal axis identifiers

Notes: The lowest possible value for <Acceleration> is 0.

OAC changes the value of the Current open-loop acceleration parameter (ID 0x7000202) in volatile memory (can be saved as power-on default with WPA (p. 190), can also be changed with SPA (p. 175) and SEP (p. 173)).

The maximum value which can be set with the OAC command is given by the Maximum open-loop

acceleration parameter, ID 0x7000205 (can be changed with SPA (p. 175) and SEP (p. 173)).

OAC? (Get Open-Loop Acceleration)

Description: Get the current value of open-loop acceleration.

If all arguments are omitted, gets current value of all axes.

Format: OAC? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the current active open-loop acceleration value in step cycles / s².

OAD (Open-Loop Analog Driving)

Description: Open-loop analog driving of the given PiezoWalk channel.

Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

Format: OAD {PiezoWalkChanID Vol}

Arguments <PiezoWalkChanID> is one PiezoWalk channel

<Vol> is the feed voltage amplitude in V. (See "Motion Modes" (p. 56) for details).

The allowable range is between -55 and 55.

The sign determines the motion direction.

Response: none

Troubleshooting: Illegal PiezoWalk channel identifier; the PiezoWalk channel is not in the Relaxed state (RNP (p. 168) required); the servo is on for the axis; joystick is enabled for the axis

Notes:

Analog driving means a motion with highest motion resolution. All piezos are in contact with the runner and move in the same direction. To achieve this, all the piezos are driven by the same "feed" voltage.

In open-loop operation, an RNP command must be sent each time the motion mode is to be changed from nanostepping motion (OSM command (p. 163)) to analog motion (OAD command) and vice versa. RNP brings the drive to a full-holding-force, zero-drive-voltage *Relaxed* state.

The first OAD sent for a NEXACT® linear drive which is in the *Relaxed* state prepares the drive for analog motion (brings it to the *Analog* state) before the actual motion is done. Once the drive is in the *Analog* state, each subsequent OAD motion will be executed immediately.

The first OAD after a change of motion mode and the RNP procedure can take up to four times the slewrate value (parameter ID 0x7000002; can be changed with SPA (p. 175) and SEP (p. 173)).

Note that the OAD command does not use the trajectory generator as all other move commands do, but OAD motion is determined by the slewrate value only.

After open-loop analog motion was done with OAD, an RNP command must be sent first before the servo can be switched on with SVO (p. 183). See "Modes of Operation" (p. 54) and "Example for Commanding Motion" (p. 20) for more information and an example.

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) and the SRG? command (p. 178). See "Changing Motion and Servo Mode" (p. 59) for more information.

Motion commands like OAD are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

OAD? (Get Voltage for Open-Loop Analog Motion)

Description: Reads last-commanded open-loop analog-driving voltage of a given PiezoWalk channel.

Format: OAD? [{PiezoWalkChanID}]

Arguments: <PiezoWalkChanID> is one PiezoWalk channel

Response: {<PiezoWalkChanID>="<float> LF}

where

<float> is the last-commanded feed voltage amplitude in V

Troubleshooting: Illegal PiezoWalk channel identifier

ODC (Set Open-Loop Deceleration)

Description: Set open-loop deceleration of given axes.

The ODC setting only takes effect when the given axis is in open-loop operation (servo off).

ODC can be changed while the axis is moving.

Format: ODC {<AxisID> <Deceleration>}

Arguments: <AxisID> is one axis of the controller

<Deceleration> is the open-loop deceleration value in step cycles/s².

Response: none

Troubleshooting: Illegal axis identifiers

Notes: The lowest possible value for <Deceleration> is 0.

ODC changes the value of the Current open-loop deceleration parameter (ID 0x7000203) in volatile memory (can be saved as power-on default with WPA (p. 190), can also be changed with SPA (p. 175) and SEP (p. 173)).

The maximum value which can be set with the ODC command is given by the Maximum open-loop deceleration parameter, ID 0x7000206 (can be changed with SPA (p. 175) and SEP (p. 173)).

ODC? (Get Open-Loop Deceleration)

Description: Get the current value of the open-loop deceleration.

If all arguments are omitted, gets current value of all axes.

Format: ODC? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the current active open-loop deceleration value in step cycles / s².

OMA (Absolute Open-Loop Motion)

Description: Commands specified axis to the given absolute position. Motion is realized in open-loop nanostepping mode.

Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

With OMA there is no position control (i.e. the target position is not maintained by any control loop). Due to the motion profile (velocity, acceleration), there will typically be an overshoot. The E-861 counts the overshoot steps, and the axis moves back the corresponding number of steps.

Caution: Do not use this command if no sensor is present in your system.

Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: OMA {<AxisID> <Position>}

Arguments: <AxisID> is one axis of the controller

<Position> is the new absolute target position in physical units, float

Response: none

Troubleshooting: Illegal axis identifier; the axis is not in the Relaxed state (RNP (p. 168) required); the servo is on for the axis; joystick is enabled for the axis

Notes: The velocity for open-loop nanostepping motion depends on the step size and on the step frequency. The step size is given by the amplitude of the feed voltage which can be set with SSA (p. 180) and queried with SSA? (p. 180). The step frequency can be set with OVL (p. 165) and queried with OVL? (p. 166).

In open-loop operation, an RNP command must be sent each time the motion mode is to be changed from nanostepping motion (OMA, OMR (p. 161) or OSM command (p. 163)) to analog motion (OAD (p. 155) command) and vice versa.

RNP brings the drive to a full-holding-force, zero-drive-voltage *Relaxed* state.

See "Modes of Operation" (p. 54) and "Example for Commanding Motion" (p. 20) for more information and an example.

The first OMA sent for a NEXACT® linear drive which is in the Relaxed state prepares the drive for nanostepping motion (brings it to the *In Motion* state) before the actual motion is done. Once the drive is in the *In Motion* state, each subsequent OMA motion will be executed immediately.

Note that a second OMA command cannot be processed as long as a motion commanded with a first OMA or OMR is still performed.

The first OMA after a change of motion mode and the RNP procedure can take up to four times the slewrate value (parameter ID 0x7000002; can be changed with SPA (p. 175) and SEP (p. 173)).

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) and the SRG? command (p. 178). See "Changing Motion and Servo Mode" (p. 59) for more information.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Motion commands like OMA are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

OMA? (Get Open-Loop Target Position)

Description: Returns last valid commanded open-loop target position. The open-loop target position is changed by OMA (p. 158) and OMR (p. 161).

Note that OMA? gets the commanded positions. Use POS? (p. 167) to get the current positions.

Format: OMA? {[<AxisID>]}

Arguments: <AxisID> is one axis of the controller

<Position> is the last commanded open-loop target position in physical units. Format of <Position> is floating point number.

Response: {<AxisID>="<Position>LF}

Notes: OMA? gets the commanded positions. Use POS? (p. 167) to get the current positions. Note that if servo is enabled, OMA? does not deliver the last commanded position, but 0.

OMR (Relative Open-Loop Motion)

Description: Commands specified axis to a position relative to the last commanded open-loop target position. The new open-loop target position is calculated by adding the given value <Distance> to the last commanded target value.
Motion is realized in nanostepping mode.

Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

With OMR there is no position control (i.e. the target position is not maintained by a control loop). Due to the motion profile (velocity, acceleration), there will typically be an overshoot. The E-861 counts the overshoot steps, and the axis moves back the corresponding number of steps.

Caution: Do not use this command if no sensor is present in your system.

Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: OMR {<AxisID> <Distance>}

Arguments: <AxisID> is one axis of the controller

<Distance> is added to the last commanded open-loop target position. The sum is set as new open-loop target position in physical units. Format of <Distance> is floating point number.

Response: none

Troubleshooting: Illegal axis identifier; the axis is not in the Relaxed state (RNP (p. 168) required); the servo is on for the axis; joystick is enabled for the axis

Notes:

The velocity for open-loop nanostepping motion depends on the step size and on the step frequency. The step size is given by the amplitude of the feed voltage which can be set with SSA (p. 180) and queried with SSA? (p. 180). The step frequency can be set with OVL (p. 165) and queried with OVL? (p. 166).

In open-loop operation, an RNP command must be sent each time the motion mode is to be changed from nanostepping motion (OMA (p. 158), OMR or OSM command (p. 163)) to analog motion (OAD (p. 155) command) and vice versa. RNP brings the drive to a full-holding-force, zero-drive-voltage *Relaxed* state. See "Modes of Operation" (p. 54) and "Example for Commanding Motion" (p. 20) for more information and an example.

The first OMR sent for a NEXACT® linear drive which is in the *Relaxed* state prepares the drive for nanostepping motion (brings it to the *In Motion* state) before the actual motion is done. Once the drive is in the *In Motion* state, each subsequent OMR motion will be executed immediately.

Note that a second OMR command cannot be processed as long as a motion commanded with a first OMR or OMA is still performed.

The first OMR after a change of motion mode and the RNP procedure can take up to four times the slewrate value (parameter ID 0x7000002; can be changed with SPA (p. 175) and SEP (p. 173)).

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) and the SRG? command (p. 178). See "Changing Motion and Servo Mode" (p. 59) for more information.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Motion commands like OMR are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

ONT? (Get On Target State)

Description: Get on-target status of given axis.

If all arguments are omitted, gets status of all axes.

Format: ONT? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller.

Response: {<AxisID>}"="<uint> LF}

where

<uint> = "1" when the specified axis is on-target, "0" otherwise.

Troubleshooting: Illegal axis identifier

Notes: The detection of the on-target status differs for closed-loop and open-loop operation.

Closed-loop operation:

The on-target status is influenced by two parameters: settle window (parameter ID 0x36) and settle time (parameter ID 0x3F).

The on-target status is true when the current position is inside the settle window and stays there for at least the settle time. The settle window is centered around the target position.

Open-loop operation:

The on-target status is true when the trajectory has finished which was internally calculated for the motion.

OSM (Open-Loop Step Moving)

Description: Open-loop nanostepping motion of the given PiezoWalk channel.

Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

Format: OSM {PiezoWalkChanID Steps}

Arguments: <PiezoWalkChanID> is one PiezoWalk channel
<Steps> is the number of steps to perform

Response: none

Troubleshooting: Illegal PiezoWalk channel identifier; the PiezoWalk channel is not in the Relaxed state (RNP (p. 168) required); the servo is on for the axis; joystick is enabled for the axis

Notes: The NEXACT® linear drive performs the given number of steps of a pre-defined size and can thus cover the whole runner (i.e. the travel range is only limited by the length of the runner). Steps are commanded using floating point numbers, i.e. you can also command any part of a full step.

The velocity for open-loop nanostepping motion depends on the step size and on the step frequency. The step size is given by the amplitude of the feed voltage which can be set with SSA (p. 180) and queried with SSA? (p. 180). The step frequency can be set with OVL (p. 165) and queried with OVL? (p. 166).

With each new OSM command, the number of steps to perform is counted starting from zero (there is no adding up of steps).

In open-loop operation, an RNP command (p. 168) must be sent each time the motion mode is to be changed from nanostepping motion (OSM, OMA (p. 158) or OMR (p. 161) commands) to analog motion (OAD command (p. 155)) and vice versa. RNP brings the drive to a full-holding-force, zero-drive-voltage *Relaxed* state.

The first OSM sent for a NEXACT® linear drive which is in the *Relaxed* state prepares the drive for nanostepping motion (brings it to the *In Motion* state) before the actual motion is done. Once the drive is in the *In Motion* state, each subsequent OSM motion will be executed immediately.

The first OSM after a change of motion mode and the RNP procedure can take up to four times the slewrate value (parameter ID 0x7000002; can be changed with SPA (p. 175) and SEP (p. 173)).

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) and the SRG? command (p. 178).

See "Modes of Operation" (p. 54) for more information and "Examples for Commanding Motion (p. 20)" for an example.

The motion can be interrupted by #24 (p. 117), STP (p. 182) and HLT (p. 137).

Motion commands like OSM are not allowed when a joystick is active on the axis. See "Joystick Control" (p. 79) for details.

OVL (Set Open-Loop Velocity)

Description: Set velocity for open-loop nanostepping motion of given PiezoWalk channel.

The OVL setting only takes effect when the given axis is in open-loop operation (servo off).

OVL can be changed while the PiezoWalk channel is moving.

Format: OVL {<PiezoWalkChanID> <OpenLoopVel>}

Arguments: <PiezoWalkChanID> is one PiezoWalk channel

<OpenLoopVel> is the open-loop velocity value in [step cycles / s].

Response: none

Troubleshooting: Illegal PiezoWalk channel identifier

Notes: <OpenLoopVel> is positive or zero.

The velocity for open-loop nanostepping motion is also influenced by the step amplitude set with SSA (p. 180).

OVL changes the values of the Current open-loop velocity parameter (ID 0x7000201) in volatile memory (can also be changed with SPA (p. 175) and SEP (p. 173)).

The maximum value which can be set with the OVL command is given by the Maximum open-loop velocity parameter, ID 0x7000204 (can be changed with SPA (p. 175) and SEP (p. 173)).
On power-on, the current open-loop velocity is set by the Current open-loop velocity parameter, ID 0x7000201.

OVL? (Get Open-Loop Velocity)

Description: Get the current value of the velocity for open-loop nanostepping motion.

If all arguments are omitted, gets current values of all PiezoWalk channels.

Format: OVL? [{<PiezoWalkChanID>}]

Arguments: <PiezoWalkChanID> is one PiezoWalk channel

Response: {<PiezoWalkChanID>="<float> LF}

where

<float> is the current active velocity value for open-loop nanostepping motion, in step cycles / s.

POS (Set Real Position)

Description: Sets the current position (does not cause motion).

Format: POS { <AxisID> <Position>}

Arguments: <AxisID> is one axis of the controller.

<Position> is the new current position in physical units.

Response: none

Troubleshooting: Illegal axis identifier

Notes: Setting the current position with POS is only possible when the reference mode is set to "0", see RON (p. 170).

An axis is considered as "referenced" when the position was set with POS (for more information refer to "Referencing" (p. 51)).

The minimum and maximum commandable positions (TMN? (p. 186), TMX? (p. 187)) are not adapted when a position is set with POS.

This may result in target positions which are allowed by the software and cannot be reached by the hardware.

Also target positions are possible which can be reached by the hardware but are denied by the software.

Furthermore, the home position can be outside of the physical travel range after using POS.

POS? (Get Real Position)

Description: Returns the current axis position.

If all arguments are omitted, gets current position of all axes.

Format: POS? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller.

Response: {<AxisID>="<float> LF}

where

<float> is the current axis position in physical units

Troubleshooting: Illegal axis identifier

RBT (Reboot System)

Description: Reboot system. Controller behaves just like after power-on.

Format: RBT

Arguments: none

Response: none

RMC? (List Running Macros)

Description: List macros which are currently running.

Format: RMC?

Arguments: none

Response: {<macroname> LF}

where

<macroname> is the name of one macro which is saved on the controller and currently running. The response is an empty line when no macro is running.

RNP (Relax PiezoWalk Piezos)

Description: "Relax" the piezos of a given PiezoWalk channel without performing any motion. The aim of this procedure is to reduce all applied voltages when the final position is reached and thus to increase the lifetime of the piezos.

Format: RNP {PiezoWalkChanID Vol}

Arguments <PiezoWalkChanID> is one PiezoWalk channel

<Vol> must be 0 to set the voltages to 0 V

Response: none

Troubleshooting: Illegal PiezoWalk channel identifier; servo is on

Notes: Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

With the Relaxing procedure performed by RNP, the NEXACT® linear drive is brought to a full-holding-force, zero-drive-voltage Relaxed state.

RNP should reduce the voltages to zero without changing the position of the NEXACT® linear drive. But depending on the current load, which may lead to a small motion of the movable part of the mechanics during the RNP procedure, small changes in position can occur.

In open-loop operation, an RNP command must be sent each time the motion mode is to be changed from nanostepping motion (OMA (p. 158), OMR (p. 161), OSM (p. 163)) to analog motion (OAD (p. 155)) or vice versa.

After open-loop analog motion was done with OAD, an RNP command must be sent first before the servo can be switched on with SVO (p. 183).

The RNP procedure can take up to four times the slewrate value (parameter ID 0x70000002; can be changed with SPA (p. 175) and SEP (p. 173)).

You can query the current state of the system (E-861 and NEXACT® linear drive) using the #4 command (p. 114) and the SRG? command (p. 178).

See "Modes of Operation" (p. 54), "Changing Motion and Servo Mode (p. 59)" and "Example for Commanding Motion (p. 20)" for more information and an example.

RON (Set Reference Mode)

Description: Set reference mode of given axes.

Format: RON {<AxisID> <ReferenceOn>}

Arguments: <AxisID> is one axis of the controller.

<ReferenceOn> can be 0 or 1:

0= referencing moves with FRF (p. 133), FNL (p. 129) and FPL (p. 131) are not possible, absolute position must be set with POS (p. 166) to reference the axis.

1= FRF or FNL or FPL is required to reference the axis, usage of POS is not allowed.

1 is default.

Response: none

Troubleshooting: Illegal axis identifier

Notes: For more information refer to "Referencing" (p. 51) and "Travel Range Adjustment" (p. 92).

RON? (Get Reference Mode)

Description: Get reference mode of given axes.

Format: RON? [{ <AxisID>}]

Arguments: <AxisID> is one axis of the controller.

Response: {<AxisID>="<ReferenceOn> LF}

where

<ReferenceOn> is the current reference mode of the controller, see RON (p. 170)

Troubleshooting: Illegal axis identifier

RPA (Reset Volatile Memory Parameters)

Description: Resets the given parameter of the given item. The value from non-volatile memory is written into volatile memory.

Related commands:

With HPA? (p. 138) you can obtain a list of the available parameters. SPA (p. 175) affects the parameter settings in volatile memory, WPA (p. 190) writes parameter settings from volatile to non-volatile memory, and SEP (p. 173) writes parameter settings directly into non-volatile memory (without changing the settings in volatile memory).
See SPA for an example.

Format: RPA [{<ItemID> <PamID>}]

Arguments: <ItemID> is the item for which a parameter is to be reset. See below for details.

<PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.

Response: none

Troubleshooting: Illegal item identifier, wrong parameter ID

Notes: With the E-861, you can reset either all parameters or one single parameter with RPA.

Available item IDs and parameter IDs: An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

RTR (Set Record Table Rate)

Description: Sets the record table rate, i.e. the number of servo-loop cycles to be used in data recording operations. Settings larger than 1 make it possible to cover longer time periods.

Format: RTR <RecordTableRate>

Arguments: <RecordTableRate> is the table rate to be used for recording operations (unit: number of servo-loop cycles), must be an integer value larger than zero

Response: None

Notes: The duration of the recording can be calculated as follows:

$$\text{Rec. Duration} = \text{Servo Cycle Time} * \text{RTR value} * \text{Number of Points}$$

where

Servo Cycle Time is 20 μ s for the E-861

Number of Points is 1024 for the E-861 (length of data recorder table)

For more information see "Data Recording" (p. 88).

The record table rate set with RTR is saved in volatile memory (RAM) only.

RTR? (Get Record Table Rate)

Description: Gets the current record table rate, i.e. the number of servo-loop cycles used in data recording operations.

Format: RTR?

Arguments: None

Response: <RecordTableRate> is the table rate used for recording operations (unit: number of servo-loop cycles)

SAI? (Get List Of Current Axis Identifiers)

Description: Gets the axis identifiers.

See also "Accessible Items and Their Identifiers" (p. 53).

Format: SAI? [ALL]

Arguments: [ALL] is optional. For controllers which allow for axis deactivation, [ALL] ensures that the answer also includes the axes which are "deactivated".

Response: {<AxisID> LF}

<AxisID> is one axis of the controller.

SEP (Set Non-Volatile Memory Parameters)

Description: Set a parameter of a given item to a different value in non-volatile memory, where it becomes the new power-on default.

After parameters were set with SEP, you can use RPA (p. 171) to activate them (write them to volatile memory) without controller reboot.

Caution: This command is for setting hardware-specific parameters. Wrong values may lead to improper operation or damage of your hardware!

Related commands:

HPA? (p. 138) returns a list of the available parameters.

SPA (p. 175) writes parameter settings into volatile memory (without changing the settings in non-volatile memory).

WPA (p. 190) writes parameter settings from volatile to non-volatile memory.

See SPA for an example.

Format: SEP <Pswd> {<ItemID> <PamID> <PamValue>}

Arguments <Pswd> is the password for writing to non-volatile memory, default is "100"

<ItemID> is the item for which a parameter is to be changed in non-volatile memory. See below for details.

<PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.

<PamValue> is the value to which the given parameter of the given item is set

Response: none

Troubleshooting: Illegal item identifier, wrong parameter ID, invalid password

Notes: Warning: The number of write cycles of non-volatile memory is limited. Write default values only when necessary.

With the E-861, you can write only one single parameter per SEP command.

The GEMAC parameters (ID 0x7000010 to ID 0x700001F) cannot be changed with SEP. Use SPA and WPA instead to save their values to non-volatile memory. See "GEMAC Parameters" (p. 105) for more information.

Available item IDs and parameter IDs: An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

SEP? (Get Non-Volatile Memory Parameters)

Description: Get the value of a parameter of a given item from non-volatile memory.

With HPA? (p. 138) you can obtain a list of the available parameters and their IDs.

Format: SEP? [{<ItemID> <PamID>}]

Arguments: <ItemID> is the item for which a parameter value from non-volatile memory is to be queried. See below for details.

<PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.

Response: {<ItemID> <PamID>="<PamValue> LF}

where

<PamValue> is the value of the given parameter for the given item

Troubleshooting: Illegal item identifier, wrong parameter ID

Notes: With the E-861, you can query either all parameters or one single parameter per SEP? command.

The GEMAC parameters (ID 0x7000010 to ID 0x700001F) cannot be queried with SEP?. Use SPA? (p. 178) immediately after power-on or reboot to read the non-volatile values of these parameters. See "GEMAC Parameters" (p. 105) for more information.

Available item IDs and parameter IDs: An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

SPA (Set Volatile Memory Parameters)

Description: Set a parameter of a given item to a value in volatile memory (RAM). Parameter changes will be lost when the controller is powered down or rebooted or when the parameters are restored with RPA (p. 171).

Caution: This command is for setting hardware-specific parameters. Wrong values may lead to improper operation or damage of your hardware!

Related commands:

HPA? (p. 138) returns a list of the available parameters.

SEP (p. 173) writes parameter settings directly into non-volatile memory (without changing the settings in volatile memory).

WPA (p. 190) writes parameter settings from volatile to non-volatile memory.

RPA resets volatile memory to the value in non-volatile memory.

Format: SPA {<ItemID> <PamID> <PamValue>}

- Arguments:** <ItemID> is the item for which a parameter is to be changed in volatile memory. See below for details.
- <PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.
- <PamValue> is the value to which the given parameter of the given item is set
- Response:** none
- Troubleshooting:** Illegal item identifier, wrong parameter ID, value out of range
- Notes:** With the E-861, you can write only one single parameter per SPA command.

The GEMAC parameters with the IDs 0x7000015, 0x7000016, 0x700001C, 0x700001D, 0x700001E and 0x700001F are write-protected and cannot be changed with SPA, even though the E-861 will send no error message if you try to change those parameters anyway.

- Available item IDs and parameter IDs:** An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

- Example 1:** Send: SPA 1 0x1 100

Note: Set the P-term of the servo-loop for axis 1 to 100, parameter ID written in hexadecimal format

Send: SPA 1 1 150

Note: Sets the P-term of the servo-loop for axis 1 to 150, parameter ID written in decimal format

Example 2: The P, I and D values of the servo algorithm must be adapted to a new load applied to the connected mechanics.

Send: SPA 1 0x1 150

Note: The P-term is set to 150 for axis 1. The setting is made in volatile memory only.

Now set the I- and D-terms in volatile memory using SPA and then test the functioning of the system. If the closed-loop system performance proves satisfactory and you want to use this system configuration after the next power-on, save the parameter settings from volatile to non-volatile memory.

Send: WPA 100

Note: This command saves the values of all parameters whose password is 100 (see the list in "Controller Parameters" (p. 35)), since WPA is used without specifying any parameter.

Example 3: Send: SEP 100 1 0xA 20

Note: The maximum value of the closed-loop velocity is to be set to 20 mm/s for axis 1. The setting is made in non-volatile memory and hence is the new power-on default, but is not yet active. To use the new settings immediately, you now have to load them to volatile memory (otherwise they would become active after the next power-on or reboot of the controller).

Send: RPA

Note: The new configuration is now active.

Send: SPA? 1 0xA

Receive: 1 0xA=20.00000

Note: Check the parameter settings in volatile memory.

SPA? (Get Volatile Memory Parameters)

Description: Get the value of a parameter of a given item from volatile memory (RAM).

With HPA? (p. 138) you can obtain a list of the available parameters and their IDs.

Format: SPA? [{<ItemID> <PamID>}]

Arguments: <ItemID> is the item for which a parameter is to be queried in volatile memory. See below for details.

<PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.

Response: {<ItemID> <PamID>="<PamValue> LF}

where

<PamValue> is the value of the given parameter for the given item

Troubleshooting: Illegal item identifier, wrong parameter ID

Notes: With the E-861, you can query either all parameters or one single parameter per SPA? command.

Available item IDs and parameter IDs: An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

SRG? (Query Status Register Value)

Description: Returns register values for queried axes and register numbers.

Format: SRG? {<AxisID> <RegisterID>}

Arguments: <AxisID>: is one axis of the controller

<RegisterID>: is the ID of the specified register, see below for available registers

Response: {<AxisID><RegisterID>="<Value> LF}

where

<Value> is the value of the register, see below for details

Note: This command is identical in function to #4 (p. 114) which should be preferred when the controller is performing time-consuming tasks.

Note that this command might deliver no response as long as the controller performs a motion with the PiezoWalk Driving mode parameter 0x7001A00 set to 1, i.e. if automatic alternating of motion modes is activated and being performed.

Possible register IDs

and response values: <RegisterID> can be 1
<Value> is the bit-mapped answer and returned as the sum of the individual codes, in hexadecimal format:

Bit	15	14	13	12	11	10	9	8
Description	On Target	Is referencing	Is moving	Servo On	Transitions between motion and servo modes: Analog = 0 Relaxing = 1 Go to analog = 2 Relaxed = 3 In motion = 4 Go to motion = 5 See "Modes of Operation" (p. 54) for details.			

Bit	7	6	5	4	3	2	1	0
Description	Digital Input 4	Digital Input 3	Digital Input 2	Digital Input 1	-	Positive Limit	Reference	Negative Limit

Example: Send: SRG? 1 1

Receive 1 1=0x9405

Note: The response is given in hexadecimal format.
It means that the axis is on target, the servo is on, the axis is ready for closed-loop motion (*In motion state*), the states of the digital input lines 1 to 4 are low, and the stage is on the positive side of the reference switch (limits are not active, note that the logic of the signals is inverted in this example)

SSA (Set Step Amplitude)

Description: Set the voltage amplitude for nanostepping motion of given PiezoWalk channel. See below for details.

Format: SSA {<PiezoWalkChanID> <Vol>}

Arguments: <PiezoWalkChanID> is one PiezoWalk channel

<Vol> is the voltage amplitude for nanostepping motion, see below for details.

Response: none

Troubleshooting: Illegal PiezoWalk channel identifier

Notes: With the E-861, <Vol> gives the feed voltage amplitude which can be 0 to 55 V for NEXACT® linear drives.

SSA changes the value of the Bending Voltage parameter (ID 0x07000003) in volatile memory (can be saved as power-on default with WPA (p. 190), can also be changed with SPA (p. 175) and SEP (p. 173)).

The SSA setting takes effect for nanostepping motion in open-loop operation (servo off). Decreasing the step size will decrease the velocity for open-loop nanostepping motion. The velocity for open-loop nanostepping motion is also influenced by the open-loop velocity set with OVL (p. 165).

SSA can be used while the PiezoWalk channel is moving.

SSA? (Get Step Amplitude)

Description: Get the current value of the voltage amplitude used for nanostepping motion. See SSA (p. 180) for details about the motion affected by the current voltage amplitude setting.

If all arguments are omitted, gets current values of all PiezoWalk channels.

Format: SSA? [{<PiezoWalkChanID>}]

Arguments: <PiezoWalkChanID> is one PiezoWalk channel

Response: {<PiezoWalkChanID>="<float> LF}

where

<float> is the current active voltage amplitude in V.

STE (Start Step And Response Measurement)

Description: Starts performing a step and recording the step response for the given axis.

The data recorder configuration, i.e. the assignment of data sources and record options to the recorder tables, can be set with DRC (p. 122).

The recorded data can be read with the DRR? (p. 124) command.

Caution: Do not use this command if no sensor is present in your system. Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Format: STE <AxisID> <Amplitude>

Arguments <AxisID> is one axis of the controller

<Amplitude> is the height of the step. See below for details.

Response: none

Troubleshooting: The control value resulting from the specified step height is out of limits. Use TMN? (p. 186) and TMX? (p. 187) to ask for the current valid travel range limits for closed-loop operation.

Motion commands like STE are not allowed when the joystick is active for the axis. See "Joystick Control" (p. 79) for details.

Notes: Step response measurements provide meaningful results only in closed-loop operation.

A "step" consists of a relative move of the specified amplitude which is performed relative to the current position. The axis must not be referenced before a measurement is performed.

STP (Stop All Axes)

Description: Stops all motion abruptly. For details see the notes below.

Sets error code to 10.

This command is identical in function to #24 (p. 117) which should be preferred when the controller is performing time-consuming tasks.

Format: STP

Arguments: none

Response: none

Troubleshooting: Communication breakdown

Notes: STP stops all motion caused by move commands (MOV (p. 151), MVR (p. 153), OAD (p. 155), OMA (p. 158), OMR (p. 161), OSM (p. 163), STE (p. 181)), referencing commands (FNL (p. 129), FPL (p. 131), FRF (p. 133)) and macros (MAC (p. 146)).

After the axes are stopped, if servo is on, their target positions are set to their current positions.

HLT (p. 137) in contrast to STP stops motion with given system deceleration with regard to system inertia.

SVO (Set Servo State)

Description: Sets servo-control state for given axes (open-loop or closed-loop operation).

Format: SVO {<AxisID> <ServoState>}

Arguments: <AxisID> is one axis of the controller

<ServoState> can have the following values:

0 = servo off (open-loop operation)

1 = servo on (closed-loop operation)

Response: none

Troubleshooting: Illegal axis identifier

Caution: Do not use this command if no sensor is present in your system.

Otherwise the connected mechanics can run into the hardstop at full speed which may cause damage to your hardware setup.

Notes:

Switching the servo on includes preparation of a "relaxed" NEXACT® linear drive for closed-loop motion.

This action can take up to four times the slewrate value (parameter ID 0x7000002).

After open-loop analog motion was done with OAD, an RNP (p. 168) command must be sent first before servo can be switched on with SVO.

See "Changing Motion and Servo Mode" (p. 59) and "Example for Commanding Motion" (p. 20) for details.

When switching from open-loop to closed-loop operation, the target is set to the current position to avoid jumps of the mechanics.

Switching the servo off includes an automatic *Relaxing* procedure which brings the NEXACT® linear drive to a full-holding-force, zero-drive-voltage *Relaxed* state.

This action can take up to four times the slewrate value (parameter ID 0x7000002).

When servo is switched off while the axis is moving, the axis stops. Exception: While the axis is under joystick control (a joystick connected to the E-861 is enabled with the JON command (p. 145)), motion will continue when the servo is switched on or off for the axis.

The current servo state affects the applicable move commands:

servo-control off: use OSM (p. 163), OMA (p. 158), OMR (p. 161) and OAD (p. 155)

servo-control on: use MOV (p. 151) and MVR (p. 153).

Using a startup macro, you can configure the controller so that servo is automatically switched on upon power-on or reboot.

See "Start-Up Macro" (p. 84) for details.

SVO? (Get Servo State)

Description: Gets servo-control state of given axes.

If all arguments are omitted, gets status of all axes.

Format: SVO? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<ServoState> LF}

where

<ServoState> is the current servo state of the axis:

0 = servo off (open-loop operation)

1 = servo on (closed-loop operation)

Troubleshooting: Illegal axis identifier

TAC? (Tell Analog Channels)

Description: Get the number of installed analog lines.

Format: TAC?

Parameter: none

Response: <uint> gives the total number of analog lines.

Notes: Gets the number of analog input lines located on the I/O socket (p. 218) of the E-861 (Input 1 to Input 4). Note that these lines can also be used for digital input. See "Accessible Items and Their Identifiers" (p. 53) for more information.

TAV? (Get Analog Input Voltage)

Description: Get voltage at analog input.

Format: TAV? [{<AnalogInputID>}]

Arguments: <AnalogInputID> is the identifier of the analog input channel, see below for details

Response: <float> is the current voltage at the analog input in volts

Notes: Using the TAV? command, you can directly read the Input 1 to Input 4 lines on the I/O socket (p. 218) of the E-861. The identifiers of the lines are 1 to 4. See "Accessible Items and Their Identifiers" (p. 53) for more information.

You can record the values of the analog input lines using the DRC record option 81 (p. 122).

TIO? (Tell Digital I/O Lines)

Description: Tell number of installed digital I/O lines

Format: TIO?

Arguments: none

Response: I=<uint1>
O=<uint2>

where

<uint1> is the number of digital input lines.

<uint2> is the number of digital output lines.

Notes: The digital output lines reported by TIO? are Output 1 to Output 4. They can be set with DIO (p. 121).

The digital input lines reported by TIO? are Input 1 to Input 4. They can be read with DIO? (p. 121), #4 (p. 114) and SRG? (p. 178).

All the lines are located on the I/O socket (p. 218) of the E-861.

TMN? (Get Minimum Commandable Position)

Description: Get the minimum commandable position in physical units.

Format: TMN? [{ <AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the minimum commandable position in physical units

Note: The minimum commandable position is defined by the MAX_TRAVEL_RANGE_NEG parameter, ID 0x30.

TMX? (Get Maximum Commandable Position)

Description: Get the maximum commandable position in physical units.

Format: TMX? [{ <AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the maximum commandable position in physical units

Note: The maximum commandable position is defined by the MAX_TRAVEL_RANGE_POS parameter, ID 0x15.

TNR? (Get Number of Record Tables)

Description: Get the number of data recorder tables currently available on the controller.

Format: TNR?

Arguments: none

Response : <uint> is the number of data recorder tables which are currently available

Notes: The E-861 has 2 data recorder tables with 1024 data points per table.
For more information see "Data Recording" (p. 88).

TRS? (Indicate Reference Switch)

Description: Indicates whether axes have a reference sensor with direction sensing.

Format: TRS? [{<AxisID>}]

Arguments: <AxisID>: is one axis of the controller

Response: {<AxisID>="<uint> LF}

where

<uint> indicates whether the axis has a direction-sensing reference sensor (=1) or not (=0).

Troubleshooting: Illegal axis identifier

Notes: The E-861 firmware detects the presence or absence of a reference switch using a controller parameter (ID 0x14).
According to the value of this parameter, the E-861 enables or disables reference moves to the reference switch (FRF command (p. 133)).
Adapt the parameter value to your hardware using SPA (p. 175) or SEP (p. 173).
See "Controller Parameters" (p. 35) for more information.

VEL (Set Closed-Loop Velocity)

Description: Set velocity of given axes.

VEL can be changed while the axis is moving.

Format: VEL {<AxisID> <Velocity>}

Arguments: <AxisID> is one axis of the controller

<Velocity> is the velocity value in physical units/s.

Response: none

Troubleshooting: Illegal axis identifiers

Notes: The VEL setting only takes effect when the given axis is in closed-loop operation (servo on).

The lowest possible value for <Velocity> is 0.

VEL changes the values of the Current closed-loop

velocity parameter (ID 0x49) in volatile memory (can also be changed with SPA (p. 175) and SEP (p. 173)).

The maximum value which can be set with the VEL command is given by the Maximum closed-loop velocity parameter, ID 0xA (can be changed with SPA (p. 175) and SEP (p. 173)).

On power-on, the current closed-loop velocity is set by the Current closed-loop velocity parameter, ID 0x7000201.

VEL? (Get Closed-Loop Velocity)

Description: Get the current velocity value.

If all arguments are omitted, gets current value of all axes.

Format: VEL? [{<AxisID>}]

Arguments: <AxisID> is one axis of the controller

Response: {<AxisID>="<float> LF}

where

<float> is the current active velocity value in physical units / s.

Notes: VEL? queries the current value of the closed-loop velocity. The open-loop velocity can be queried with the OVL? command (p. 166).

WAC (Wait For Condition)

Description: Wait until a given condition of the following type occurs: a specified value is compared with a queried value according a specified rule.

Can only be used in macros.

See also MEX (p. 149).

Format: WAC <CMD?> <OP> <value>

Arguments: <CMD?> is one questioning command in its usual syntax. The answer must consist of a single value. For an example see below.

<OP> is the operator to be used. The following operators are possible:
 = <= < > >= !=

<value> is the value to be compared with the response of <CMD?>

Response: none

Example: Send: MAC BEG AMC028
 MVR 1 1
 WAC ONT? 1 = 1
 MVR 1 -1
 WAC ONT? 1 = 1
 MAC START AMC028
 MAC END
 MAC START AMC028

Note: Macro AMC028 is recorded and then started. WAC ONT? 1 = 1 waits until the answer to ONT? 1 is 1=1. To form an infinite loop, the macro calls itself.

WPA (Save Parameters To Non-Volatile Memory)

Description: Write the currently valid value of a parameter of a given item from volatile memory (RAM) to non-volatile memory. The values saved this way become the power-on defaults.

Caution: If current parameter values are incorrect, the system may malfunction. Be sure that you have the correct parameter settings before using the WPA command.

RAM settings not saved with WPA will be lost when the controller is powered down or rebooted or when RPA (p. 171) is used to restore the parameters.

With HPA? (p. 138) you can obtain a list of all available parameters.

Use SPA? (p. 175) to check the current parameter settings in volatile memory.

See SPA (p. 175) for an example.

Format: WPA <Pswd> [{<ItemID> <PamID>}]

Arguments: <Pswd> is the password for writing to non-volatile memory. See below for details.

<ItemID> is the item for which parameters are to be saved from volatile to non-volatile memory. See below for details.

<PamID> is the parameter ID, can be written in hexadecimal or decimal format. See below for details.

Response: none

Troubleshooting: Illegal item identifier, wrong parameter ID, invalid password

Notes: Parameters can be changed in volatile memory with SPA (p. 175) and SSA (p. 180).

When WPA is used without specifying any arguments except of the password, the currently valid values of all parameters affected by the specified password are saved. Otherwise only one single parameter can be saved per WPA command.

Warning: The number of write cycles of non-volatile memory is limited. Write default values only when necessary.

Valid passwords: The password for writing to non-volatile memory depends on the parameter and can be "100" or "4711". See the parameter list in "Controller Parameters" (p. 35) for the password assignment.

Available item IDs and parameter IDs: An item is an axis / a PiezoWalk channel, the identifier is always 1. See "Accessible Items and Their Identifiers" (p. 53) for more information.

Valid parameter IDs are given in "Controller Parameters" (p. 35).

10.4 Error Codes

The error codes listed here are those of the PI General Command Set. As such, some may be not relevant to your controller and will simply never occur.

Controller Errors

0	PI_CNTR_NO_ERROR	No error
1	PI_CNTR_PARAM_SYNTAX	Parameter syntax error
2	PI_CNTR_UNKNOWN_COMMAND	Unknown command
3	PI_CNTR_COMMAND_TOO_LONG	Command length out of limits or command buffer overrun
4	PI_CNTR_SCAN_ERROR	Error while scanning
5	PI_CNTR_MOVE_WITHOUT_REF_OR_NO_SERVO	Unallowable move attempted on unreferenced axis, or move attempted with servo off
6	PI_CNTR_INVALID_SGA_PARAM	Parameter for SGA not valid
7	PI_CNTR_POS_OUT_OF_LIMITS	Position out of limits
8	PI_CNTR_VEL_OUT_OF_LIMITS	Velocity out of limits
9	PI_CNTR_SET_PIVOT_NOT_POSSIBLE	Attempt to set pivot point while U,V and W not all 0
10	PI_CNTR_STOP	Controller was stopped by command
11	PI_CNTR_SST_OR_SCAN_RANGE	Parameter for SST or for one of the embedded scan algorithms out of range
12	PI_CNTR_INVALID_SCAN_AXES	Invalid axis combination for fast scan
13	PI_CNTR_INVALID_NAV_PARAM	Parameter for NAV out of range
14	PI_CNTR_INVALID_ANALOG_INPUT	Invalid analog channel
15	PI_CNTR_INVALID_AXIS_IDENTIFIER	Invalid axis identifier
16	PI_CNTR_INVALID_STAGE_NAME	Unknown stage name
17	PI_CNTR_PARAM_OUT_OF_RANGE	Parameter out of range
18	PI_CNTR_INVALID_MACRO_NAME	Invalid macro name
19	PI_CNTR_MACRO_RECORD	Error while recording macro
20	PI_CNTR_MACRO_NOT_FOUND	Macro not found
21	PI_CNTR_AXIS_HAS_NO_BRAKE	Axis has no brake
22	PI_CNTR_DOUBLE_AXIS	Axis identifier specified more than once
23	PI_CNTR_ILLEGAL_AXIS	Illegal axis



24	PI_CNTR_PARAM_NR	Incorrect number of parameters
25	PI_CNTR_INVALID_REAL_NR	Invalid floating point number
26	PI_CNTR_MISSING_PARAM	Parameter missing
27	PI_CNTR_SOFT_LIMIT_OUT_OF_RANGE	Soft limit out of range
28	PI_CNTR_NO_MANUAL_PAD	No manual pad found
29	PI_CNTR_NO_JUMP	No more step-response values
30	PI_CNTR_INVALID_JUMP	No step-response values recorded
31	PI_CNTR_AXIS_HAS_NO_REFERENCE	Axis has no reference sensor
32	PI_CNTR_STAGE_HAS_NO_LIM_SWITCH	Axis has no limit switch
33	PI_CNTR_NO_RELAY_CARD	No relay card installed
34	PI_CNTR_CMD_NOT_ALLOWED_FOR_STAGE	Command not allowed for selected stage(s)
35	PI_CNTR_NO_DIGITAL_INPUT	No digital input installed
36	PI_CNTR_NO_DIGITAL_OUTPUT	No digital output configured
37	PI_CNTR_NO_MCM	No more MCM responses
38	PI_CNTR_INVALID_MCM	No MCM values recorded
39	PI_CNTR_INVALID_CNTR_NUMBER	Controller number invalid
40	PI_CNTR_NO_JOYSTICK_CONNECTED	No joystick configured
41	PI_CNTR_INVALID_EGE_AXIS	Invalid axis for electronic gearing, axis cannot be slave
42	PI_CNTR_SLAVE_POSITION_OUT_OF_RANGE	Position of slave axis is out of range
43	PI_CNTR_COMMAND_EGE_SLAVE	Slave axis cannot be commanded directly when electronic gearing is enabled
44	PI_CNTR_JOYSTICK_CALIBRATION_FAILED	Calibration of joystick failed
45	PI_CNTR_REFERENCING_FAILED	Referencing failed
46	PI_CNTR_OPM_MISSING	OPM (Optical Power Meter) missing
47	PI_CNTR_OPM_NOT_INITIALIZED	OPM (Optical Power Meter) not initialized or cannot be initialized
48	PI_CNTR_OPM_COM_ERROR	OPM (Optical Power Meter) Communication Error
49	PI_CNTR_MOVE_TO_LIMIT_SWITCH_FAILED	Move to limit switch failed
50	PI_CNTR_REF_WITH_REF_DISABLED	Attempt to reference axis with referencing disabled
51	PI_CNTR_AXIS_UNDER_JOYSTICK_CONTROL	Selected axis is controlled by joystick



52	PI_CNTR_COMMUNICATION_ERROR	Controller detected communication error
53	PI_CNTR_DYNAMIC_MOVE_IN_PROCESS	MOV! motion still in progress
54	PI_CNTR_UNKNOWN_PARAMETER	Unknown parameter
55	PI_CNTR_NO_REP_RECORDED	No commands were recorded with REP
56	PI_CNTR_INVALID_PASSWORD	Password invalid
57	PI_CNTR_INVALID_RECORDER_CHAN	Data Record Table does not exist
58	PI_CNTR_INVALID_RECORDER_SRC_OPT	Source does not exist; number too low or too high
59	PI_CNTR_INVALID_RECORDER_SRC_CHAN	Source Record Table number too low or too high
60	PI_CNTR_PARAM_PROTECTION	Protected Param: current Command Level (CCL) too low
61	PI_CNTR_AUTOZERO_RUNNING	Command execution not possible while Autozero is running
62	PI_CNTR_NO_LINEAR_AXIS	Autozero requires at least one linear axis
63	PI_CNTR_INIT_RUNNING	Initialization still in progress
64	PI_CNTR_READ_ONLY_PARAMETER	Parameter is read-only
65	PI_CNTR_PAM_NOT_FOUND	Parameter not found in non-volatile memory
66	PI_CNTR_VOL_OUT_OF_LIMITS	Voltage out of limits
67	PI_CNTR_WAVE_TOO_LARGE	Not enough memory available for requested wave curve
68	PI_CNTR_NOT_ENOUGH_DDL_MEMORY	Not enough memory available for DDL table; DDL cannot be started
69	PI_CNTR_DDL_TIME_DELAY_TOO_LARGE	Time delay larger than DDL table; DDL cannot be started
70	PI_CNTR_DIFFERENT_ARRAY_LENGTH	The requested arrays have different lengths; query them separately
71	PI_CNTR_GEN_SINGLE_MODE_RESTART	Attempt to restart the generator while it is running in single step mode
72	PI_CNTR_ANALOG_TARGET_ACTIVE	Motion commands and wave generator activation are not allowed when analog target is active



73	PI_CNTR_WAVE_GENERATOR_ACTIVE	Motion commands are not allowed when wave generator is active
74	PI_CNTR_AUTOZERO_DISABLED	No sensor channel or no piezo channel connected to selected axis (sensor and piezo matrix)
75	PI_CNTR_NO_WAVE_SELECTED	Generator started (WGO) without having selected a wave table (WSL).
76	PI_CNTR_IF_BUFFER_OVERRUN	Interface buffer did overrun and command couldn't be received correctly
77	PI_CNTR_NOT_ENOUGH_RECORDED_DATA	Data Record Table does not hold enough recorded data
78	PI_CNTR_TABLE_DEACTIVATED	Data Record Table is not configured for recording
79	PI_CNTR_OPENLOOP_VALUE_SET_WHEN_SERVO_ON	Open-loop commands (SVA, SVR) are not allowed when servo is on
80	PI_CNTR_RAM_ERROR	Hardware error affecting RAM
81	PI_CNTR_MACRO_UNKNOWN_COMMAND	Not macro command
82	PI_CNTR_MACRO_PC_ERROR	Macro counter out of range
83	PI_CNTR_JOYSTICK_ACTIVE	Joystick is active
84	PI_CNTR_MOTOR_IS_OFF	Motor is off
85	PI_CNTR_ONLY_IN_MACRO	Macro-only command
86	PI_CNTR_JOYSTICK_UNKNOWN_AXIS	Invalid joystick axis
87	PI_CNTR_JOYSTICK_UNKNOWN_ID	Joystick unknown
88	PI_CNTR_REF_MODE_IS_ON	Move without referenced stage
89	PI_CNTR_NOT_ALLOWED_IN_CURRENT_MOTION_MODE	Command not allowed in current motion mode
90	PI_CNTR_DIO_AND_TRACING_NOT_POSSIBLE	No tracing possible while digital IOs are used on this HW revision. Reconnect to switch operation mode.
91	PI_CNTR_COLLISION	Move not possible, would cause collision
92	PI_CNTR_SLAVE_NOT_FAST_ENOUGH	Stage is not capable of following the master. Check the gear ratio.
100	PI_LABVIEW_ERROR	PI LabVIEW driver reports error. See source control for details.
200	PI_CNTR_NO_AXIS	No stage connected to axis



201	PI_CNTR_NO_AXIS_PARAM_FILE	File with axis parameters not found
202	PI_CNTR_INVALID_AXIS_PARAM_FILE	Invalid axis parameter file
203	PI_CNTR_NO_AXIS_PARAM_BACKUP	Backup file with axis parameters not found
204	PI_CNTR_RESERVED_204	PI internal error code 204
205	PI_CNTR_SMO_WITH_SERVO_ON	SMO with servo on
206	PI_CNTR_UUDECODE_INCOMPLETE_HEADER	uudecode: incomplete header
207	PI_CNTR_UUDECODE_NOTHING_TO_DECODE	uudecode: nothing to decode
208	PI_CNTR_UUDECODE_ILLEGAL_FORMAT	uudecode: illegal UUE format
209	PI_CNTR_CRC32_ERROR	CRC32 error
210	PI_CNTR_ILLEGAL_FILENAME	Illegal file name (must be 8-0 format)
211	PI_CNTR_FILE_NOT_FOUND	File not found on controller
212	PI_CNTR_FILE_WRITE_ERROR	Error writing file on controller
213	PI_CNTR_DTR_HINDERS_VELOCITY_CHANGE	VEL command not allowed in DTR Command Mode
214	PI_CNTR_POSITION_UNKNOWN	Position calculations failed
215	PI_CNTR_CONN_POSSIBLY_BROKEN	The connection between controller and stage may be broken
216	PI_CNTR_ON_LIMIT_SWITCH	The connected stage has driven into a limit switch, some controllers need CLR to resume operation
217	PI_CNTR_UNEXPECTED_STRUT_STOP	Strut test command failed because of an unexpected strut stop
218	PI_CNTR_POSITION_BASED_ON_ESTIMATION	While MOV! is running position can only be estimated!
219	PI_CNTR_POSITION_BASED_ON_INTERPOLATION	Position was calculated during MOV motion
230	PI_CNTR_INVALID_HANDLE	Invalid handle
231	PI_CNTR_NO_BIOS_FOUND	No bios found
232	PI_CNTR_SAVE_SYS_CFG_FAILED	Save system configuration failed
233	PI_CNTR_LOAD_SYS_CFG_FAILED	Load system configuration failed
301	PI_CNTR_SEND_BUFFER_OVERFLOW	Send buffer overflow
302	PI_CNTR_VOLTAGE_OUT_OF_LIMITS	Voltage out of limits
303	PI_CNTR_OPEN_LOOP_MOTION_SET_WHEN_SERVO_ON	Open-loop motion attempted when servo ON



304	PI_CNTR_RECEIVING_BUFFER_OVERFLOW	Received command is too long
305	PI_CNTR_EEPROM_ERROR	Error while reading/writing EEPROM
306	PI_CNTR_I2C_ERROR	Error on I2C bus
307	PI_CNTR_RECEIVING_TIMEOUT	Timeout while receiving command
308	PI_CNTR_TIMEOUT	A lengthy operation has not finished in the expected time
309	PI_CNTR_MACRO_OUT_OF_SPACE	Insufficient space to store macro
310	PI_CNTR_EUI_OLDVERSION_CFGDATA	Configuration data has old version number
311	PI_CNTR_EUI_INVALID_CFGDATA	Invalid configuration data
333	PI_CNTR_HARDWARE_ERROR	Internal hardware error
400	PI_CNTR_WAV_INDEX_ERROR	Wave generator index error
401	PI_CNTR_WAV_NOT_DEFINED	Wave table not defined
402	PI_CNTR_WAV_TYPE_NOT_SUPPORTED	Wave type not supported
403	PI_CNTR_WAV_LENGTH_EXCEEDS_LIMIT	Wave length exceeds limit
404	PI_CNTR_WAV_PARAMETER_NR	Wave parameter number error
405	PI_CNTR_WAV_PARAMETER_OUT_OF_LIMIT	Wave parameter out of range
406	PI_CNTR_WGO_BIT_NOT_SUPPORTED	WGO command bit not supported
502	PI_CNTR_REDUNDANCY_LIMIT_EXCEEDED	Position consistency check failed
503	PI_CNTR_COLLISION_SWITCH_ACTIVATED	Hardware collision sensor(s) are activated
504	PI_CNTR_FOLLOWING_ERROR	Strut following error occurred, e.g. caused by overload or encoder failure
555	PI_CNTR_UNKNOWN_ERROR	BasMac: unknown controller error
601	PI_CNTR_NOT_ENOUGH_MEMORY	not enough memory
602	PI_CNTR_HW_VOLTAGE_ERROR	hardware voltage error
603	PI_CNTR_HW_TEMPERATURE_ERROR	hardware temperature out of range
1000	PI_CNTR_TOO_MANY_NESTED_MACROS	Too many nested macros
1001	PI_CNTR_MACRO_ALREADY_DEFINED	Macro already defined
1002	PI_CNTR_NO_MACRO_RECORDING	Macro recording not activated
1003	PI_CNTR_INVALID_MAC_PARAM	Invalid parameter for MAC
1004	PI_CNTR_RESERVED_1004	PI internal error code 1004



1005	PI_CNTR_CONTROLLER_BUSY	Controller is busy with some lengthy operation (e.g. reference move, fast scan algorithm)
2000	PI_CNTR_ALREADY_HAS_SERIAL_NUMBER	Controller already has a serial number
4000	PI_CNTR_SECTOR_ERASE_FAILED	Sector erase failed
4001	PI_CNTR_FLASH_PROGRAM_FAILED	Flash program failed
4002	PI_CNTR_FLASH_READ_FAILED	Flash read failed
4003	PI_CNTR_HW_MATCHCODE_ERROR	HW match code missing/invalid
4004	PI_CNTR_FW_MATCHCODE_ERROR	FW match code missing/invalid
4005	PI_CNTR_HW_VERSION_ERROR	HW version missing/invalid
4006	PI_CNTR_FW_VERSION_ERROR	FW version missing/invalid
4007	PI_CNTR_FW_UPDATE_ERROR	FW update failed
5000	PI_CNTR_INVALID_PCC_SCAN_DATA	PicoCompensation scan data is not valid
5001	PI_CNTR_PCC_SCAN_RUNNING	PicoCompensation is running, some actions cannot be executed during scanning/recording
5002	PI_CNTR_INVALID_PCC_AXIS	Given axis cannot be defined as PPC axis
5003	PI_CNTR_PCC_SCAN_OUT_OF_RANGE	Defined scan area is larger than the travel range
5004	PI_CNTR_PCC_TYPE_NOT_EXISTING	Given PicoCompensation type is not defined
5005	PI_CNTR_PCC_PAM_ERROR	PicoCompensation parameter error
5006	PI_CNTR_PCC_TABLE_ARRAY_TOO_LARGE	PicoCompensation table is larger than maximum table length
5100	PI_CNTR_NEXLINE_ERROR	Common error in NEXLINE® firmware module
5101	PI_CNTR_CHANNEL_ALREADY_USED	Output channel for NEXLINE® cannot be redefined for other usage
5102	PI_CNTR_NEXLINE_TABLE_TOO_SMALL	Memory for NEXLINE® signals is too small
5103	PI_CNTR_RNP_WITH_SERVO_ON	RNP cannot be executed if axis is in closed loop
5104	PI_CNTR_RNP_NEEDED	Relax procedure (RNP) needed
5200	PI_CNTR_AXIS_NOT_CONFIGURED	Axis must be configured for this action

Interface Errors

0	COM_NO_ERROR	No error occurred during function call
-1	COM_ERROR	Error during com operation (could not be specified)
-2	SEND_ERROR	Error while sending data
-3	REC_ERROR	Error while receiving data
-4	NOT_CONNECTED_ERROR	Not connected (no port with given ID open)
-5	COM_BUFFER_OVERFLOW	Buffer overflow
-6	CONNECTION_FAILED	Error while opening port
-7	COM_TIMEOUT	Timeout error
-8	COM_MULTILINE_RESPONSE	There are more lines waiting in buffer
-9	COM_INVALID_ID	There is no interface or DLL handle with the given ID
-10	COM_NOTIFY_EVENT_ERROR	Event/message for notification could not be opened
-11	COM_NOT_IMPLEMENTED	Function not supported by this interface type
-12	COM_ECHO_ERROR	Error while sending "echoed" data
-13	COM_GPIB_EDVR	IEEE488: System error
-14	COM_GPIB_ECIC	IEEE488: Function requires GPIB board to be CIC
-15	COM_GPIB_ENOL	IEEE488: Write function detected no listeners
-16	COM_GPIB_EADR	IEEE488: Interface board not addressed correctly
-17	COM_GPIB_EARG	IEEE488: Invalid argument to function call
-18	COM_GPIB_ESAC	IEEE488: Function requires GPIB board to be SAC
-19	COM_GPIB_EABO	IEEE488: I/O operation aborted
-20	COM_GPIB_ENEB	IEEE488: Interface board not found
-21	COM_GPIB_EDMA	IEEE488: Error performing DMA

-22	COM_GPIB_EOIP	IEEE488: I/O operation started before previous operation completed
-23	COM_GPIB_ECAP	IEEE488: No capability for intended operation
-24	COM_GPIB_EFSO	IEEE488: File system operation error
-25	COM_GPIB_EBUS	IEEE488: Command error during device call
-26	COM_GPIB_ESTB	IEEE488: Serial poll-status byte lost
-27	COM_GPIB_ESRQ	IEEE488: SRQ remains asserted
-28	COM_GPIB_ETAB	IEEE488: Return buffer full
-29	COM_GPIB_ELCK	IEEE488: Address or board locked
-30	COM_RS_INVALID_DATA_BITS	RS-232: 5 data bits with 2 stop bits is an invalid combination, as is 6, 7, or 8 data bits with 1.5 stop bits
-31	COM_ERROR_RS_SETTINGS	RS-232: Error configuring the COM port
-32	COM_INTERNAL_RESOURCES_ERROR	Error dealing with internal system resources (events, threads, ...)
-33	COM_DLL_FUNC_ERROR	A DLL or one of the required functions could not be loaded
-34	COM_FTDIUSB_INVALID_HANDLE	FTDIUSB: invalid handle
-35	COM_FTDIUSB_DEVICE_NOT_FOUND	FTDIUSB: device not found
-36	COM_FTDIUSB_DEVICE_NOT_OPENED	FTDIUSB: device not opened
-37	COM_FTDIUSB_IO_ERROR	FTDIUSB: IO error
-38	COM_FTDIUSB_INSUFFICIENT_RESOURCES	FTDIUSB: insufficient resources
-39	COM_FTDIUSB_INVALID_PARAMETER	FTDIUSB: invalid parameter
-40	COM_FTDIUSB_INVALID_BAUD_RATE	FTDIUSB: invalid baud rate
-41	COM_FTDIUSB_DEVICE_NOT_OPENED_FOR_ERASE	FTDIUSB: device not opened for erase
-42	COM_FTDIUSB_DEVICE_NOT_OPENED_FOR_WRITE	FTDIUSB: device not opened for write
-43	COM_FTDIUSB_FAILED_TO_WRITE_DEVICE	FTDIUSB: failed to write device
-44	COM_FTDIUSB_EEPROM_READ_FAILED	FTDIUSB: EEPROM read failed
-45	COM_FTDIUSB_EEPROM_WRITE_FAILED	FTDIUSB: EEPROM write failed



-46	COM_FTDIUSB_EEPROM_ERASE_FAILED	FTDIUSB: EEPROM erase failed
-47	COM_FTDIUSB_EEPROM_NOT_PRESENT	FTDIUSB: EEPROM not present
-48	COM_FTDIUSB_EEPROM_NOT_PROGRAMMED	FTDIUSB: EEPROM not programmed
-49	COM_FTDIUSB_INVALID_ARGS	FTDIUSB: invalid arguments
-50	COM_FTDIUSB_NOT_SUPPORTED	FTDIUSB: not supported
-51	COM_FTDIUSB_OTHER_ERROR	FTDIUSB: other error
-52	COM_PORT_ALREADY_OPEN	Error while opening the COM port: was already open
-53	COM_PORT_CHECKSUM_ERROR	Checksum error in received data from COM port
-54	COM_SOCKET_NOT_READY	Socket not ready, you should call the function again
-55	COM_SOCKET_PORT_IN_USE	Port is used by another socket
-56	COM_SOCKET_NOT_CONNECTED	Socket not connected (or not valid)
-57	COM_SOCKET_TERMINATED	Connection terminated (by peer)
-58	COM_SOCKET_NO_RESPONSE	Can't connect to peer
-59	COM_SOCKET_INTERRUPTED	Operation was interrupted by a nonblocked signal
-60	COM_PCI_INVALID_ID	No device with this ID is present
-61	COM_PCI_ACCESS_DENIED	Driver could not be opened (on Vista: run as administrator!)

DLL Errors

-1001	PI_UNKNOWN_AXIS_IDENTIFIER	Unknown axis identifier
-1002	PI_NR_NAV_OUT_OF_RANGE	Number for NAV out of range--must be in [1,10000]
-1003	PI_INVALID_SGA	Invalid value for SGA--must be one of 1, 10, 100, 1000
-1004	PI_UNEXPECTED_RESPONSE	Controller sent unexpected response
-1005	PI_NO_MANUAL_PAD	No manual control pad installed, calls to SMA and related commands are not allowed

-1006	PI_INVALID_MANUAL_PAD_KNOB	Invalid number for manual control pad knob
-1007	PI_INVALID_MANUAL_PAD_AXIS	Axis not currently controlled by a manual control pad
-1008	PI_CONTROLLER_BUSY	Controller is busy with some lengthy operation (e.g. reference move, fast scan algorithm)
-1009	PI_THREAD_ERROR	Internal error--could not start thread
-1010	PI_IN_MACRO_MODE	Controller is (already) in macro mode--command not valid in macro mode
-1011	PI_NOT_IN_MACRO_MODE	Controller not in macro mode--command not valid unless macro mode active
-1012	PI_MACRO_FILE_ERROR	Could not open file to write or read macro
-1013	PI_NO_MACRO_OR_EMPTY	No macro with given name on controller, or macro is empty
-1014	PI_MACRO_EDITOR_ERROR	Internal error in macro editor
-1015	PI_INVALID_ARGUMENT	One or more arguments given to function is invalid (empty string, index out of range, ...)
-1016	PI_AXIS_ALREADY_EXISTS	Axis identifier is already in use by a connected stage
-1017	PI_INVALID_AXIS_IDENTIFIER	Invalid axis identifier
-1018	PI_COM_ARRAY_ERROR	Could not access array data in COM server
-1019	PI_COM_ARRAY_RANGE_ERROR	Range of array does not fit the number of parameters
-1020	PI_INVALID_SPA_CMD_ID	Invalid parameter ID given to SPA or SPA?
-1021	PI_NR_AVG_OUT_OF_RANGE	Number for AVG out of range--must be >0
-1022	PI_WAV_SAMPLES_OUT_OF_RANGE	Incorrect number of samples given to WAV
-1023	PI_WAV_FAILED	Generation of wave failed
-1024	PI_MOTION_ERROR	Motion error: position error too large, servo is switched off automatically
-1025	PI_RUNNING_MACRO	Controller is (already) running a macro
-1026	PI_PZT_CONFIG_FAILED	Configuration of PZT stage or amplifier failed



-1027	PI_PZT_CONFIG_INVALID_PARAMS	Current settings are not valid for desired configuration
-1028	PI_UNKNOWN_CHANNEL_IDENTIFIER	Unknown channel identifier
-1029	PI_WAVE_PARAM_FILE_ERROR	Error while reading/writing wave generator parameter file
-1030	PI_UNKNOWN_WAVE_SET	Could not find description of wave form. Maybe WG.INI is missing?
-1031	PI_WAVE_EDITOR_FUNC_NOT_LOADED	The WGWaveEditor DLL function was not found at startup
-1032	PI_USER_CANCELLED	The user cancelled a dialog
-1033	PI_C844_ERROR	Error from C-844 Controller
-1034	PI_DLL_NOT_LOADED	DLL necessary to call function not loaded, or function not found in DLL
-1035	PI_PARAMETER_FILE_PROTECTED	The open parameter file is protected and cannot be edited
-1036	PI_NO_PARAMETER_FILE_OPENED	There is no parameter file open
-1037	PI_STAGE_DOES_NOT_EXIST	Selected stage does not exist
-1038	PI_PARAMETER_FILE_ALREADY_OPENED	There is already a parameter file open. Close it before opening a new file
-1039	PI_PARAMETER_FILE_OPEN_ERROR	Could not open parameter file
-1040	PI_INVALID_CONTROLLER_VERSION	The version of the connected controller is invalid
-1041	PI_PARAM_SET_ERROR	Parameter could not be set with SPA--parameter not defined for this controller!
-1042	PI_NUMBER_OF_POSSIBLE_WAVES_EXCEEDED	The maximum number of wave definitions has been exceeded
-1043	PI_NUMBER_OF_POSSIBLE_GENERATORS_EXCEEDED	The maximum number of wave generators has been exceeded
-1044	PI_NO_WAVE_FOR_AXIS_DEFINED	No wave defined for specified axis
-1045	PI_CANT_STOP_OR_START_WAV	Wave output to axis already stopped/started
-1046	PI_REFERENCE_ERROR	Not all axes could be referenced



-1047	PI_REQUIRED_WAVE_NOT_FOUND	Could not find parameter set required by frequency relation
-1048	PI_INVALID_SPP_CMD_ID	Command ID given to SPP or SPP? is not valid
-1049	PI_STAGE_NAME_ISNT_UNIQUE	A stage name given to CST is not unique
-1050	PI_FILE_TRANSFER_BEGIN_MISSING	A uuencoded file transferred did not start with "begin" followed by the proper filename
-1051	PI_FILE_TRANSFER_ERROR_TEMP_FILE	Could not create/read file on host PC
-1052	PI_FILE_TRANSFER_CRC_ERROR	Checksum error when transferring a file to/from the controller
-1053	PI_COULDNT_FIND_PISTAGES_DAT	The PiStages.dat database could not be found. This file is required to connect a stage with the CST command
-1054	PI_NO_WAVE_RUNNING	No wave being output to specified axis
-1055	PI_INVALID_PASSWORD	Invalid password
-1056	PI_OPM_COM_ERROR	Error during communication with OPM (Optical Power Meter), maybe no OPM connected
-1057	PI_WAVE_EDITOR_WRONG_PARAMNUM	WaveEditor: Error during wave creation, incorrect number of parameters
-1058	PI_WAVE_EDITOR_FREQUENCY_OUT_OF_RANGE	WaveEditor: Frequency out of range
-1059	PI_WAVE_EDITOR_WRONG_IP_VALUE	WaveEditor: Error during wave creation, incorrect index for integer parameter
-1060	PI_WAVE_EDITOR_WRONG_DP_VALUE	WaveEditor: Error during wave creation, incorrect index for floating point parameter
-1061	PI_WAVE_EDITOR_WRONG_ITEM_VALUE	WaveEditor: Error during wave creation, could not calculate value
-1062	PI_WAVE_EDITOR_MISSING_GRAPH_COMPONENT	WaveEditor: Graph display component not installed



-1063	PI_EXT_PROFILE_UNALLOWED_CMD	User Profile Mode: Command is not allowed, check for required preparatory commands
-1064	PI_EXT_PROFILE_EXPECTING_MOTION_ERROR	User Profile Mode: First target position in User Profile is too far from current position
-1065	PI_EXT_PROFILE_ACTIVE	Controller is (already) in User Profile Mode
-1066	PI_EXT_PROFILE_INDEX_OUT_OF_RANGE	User Profile Mode: Block or Data Set index out of allowed range
-1067	PI_PROFILE_GENERATOR_NO_PROFILE	ProfileGenerator: No profile has been created yet
-1068	PI_PROFILE_GENERATOR_OUT_OF_LIMITS	ProfileGenerator: Generated profile exceeds limits of one or both axes
-1069	PI_PROFILE_GENERATOR_UNKNOWN_PARAMETER	ProfileGenerator: Unknown parameter ID in Set/Get Parameter command
-1070	PI_PROFILE_GENERATOR_PAR_OUT_OF_RANGE	ProfileGenerator: Parameter out of allowed range
-1071	PI_EXT_PROFILE_OUT_OF_MEMORY	User Profile Mode: Out of memory
-1072	PI_EXT_PROFILE_WRONG_CLUSTER	User Profile Mode: Cluster is not assigned to this axis
-1073	PI_UNKNOWN_CLUSTER_IDENTIFIER	Unknown cluster identifier The installed device driver doesn't match the required version. Please see the documentation to determine the required device driver version.
-1074	PI_INVALID_DEVICE_DRIVER_VERSION	
-1075	PI_INVALID_LIBRARY_VERSION	The library used doesn't match the required version. Please see the documentation to determine the required library version.
-1076	PI_INTERFACE_LOCKED	The interface is currently locked by another function. Please try again later.
-1077	PI_PARAM_DAT_FILE_INVALID_VERSION	Version of parameter DAT file does not match the required version. Current files are available at www.pi.ws .

-1078 PI_CANNOT_WRITE_TO_PARAM_DAT_FILE

Cannot write to parameter
DAT file to store user defined
stage type.

-1079 PI_CANNOT_CREATE_PARAM_DAT_FILE

Cannot create parameter
DAT file to store user defined
stage type.

-1080 PI_PARAM_DAT_FILE_INVALID_REVISION

Parameter DAT file does not
have correct revision.

-1081 PI_USERSTAGES_DAT_FILE_INVALID_REVISION

User stages DAT file does
not have correct revision.

11 Troubleshooting

Communication with controller does not work

Communication cable is wrong or defective

⇒ Check cable. Does it work properly with another device?

For RS-232, a null-modem cable must be used.

The interface is not configured correctly

⇒ With the RS-232 interface, check port and baud rate (depending on your controller, the baud rate may be set via DIP switches on the front panel or via a controller parameter).

It is recommended that the host PC have a "genuine" RS-232 interface on board.

If the host PC uses a USB-to-serial adapter instead, data loss could occur during communication, especially when transferring large amounts of data.

⇒ The USB drivers will make the USB interface appear to all software on the host PC as a new COM port. That port will be present only when the controller is connected via USB and powered on.

⇒ All controllers in a daisy chain network must be set to the same baud rate.

⇒ Up to 16 E-861 controllers can be controlled from a single host computer interface. The RS-232 output stages of some PCs may not be capable of driving more than 6 units; if this is a problem use USB to interface with the PC.

⇒ The RS-232 cable must never be connected to a PC at the same time an USB cable is connected.

Another program is using the interface

⇒ Close the other program.

Specific software has problems

⇒ See if the system works with some other software, e.g. a terminal or development environment. You can, for example, test the communication by simply starting a terminal program, e.g. PI Terminal, and entering commands like *IDN? or HLP?. Note that multi-character commands are transferred as terminated by a LF (line feed) character and are executed only after the LF is received.

Stage does not move

Cable not connected properly

⇒ Check the connecting cable(s)

Stage or stage cable is defective

⇒ Exchange stage with a working stage to test a new combination of controller and stage:

With E-7xx controllers, this is only possible with stages which are equipped with ID-chips.

With E-861 controllers, the encoder hardware of closed-loop systems must be identical or the parameters of the GEMAC interpolation circuit must be adapted, see "GEMAC Parameters" (p. 105) for more information.

Controller address wrong or missing

⇒ Check the current controller address (see "DIP Switch Settings").

⇒ In principle, the address of the target controller is required in every command line, even when recording macros or sending single-character commands. It can only be omitted if the target E-861 has the address 1. See "Target and Sender Address" (p. 110) for more information.

⇒ In a daisy-chain, connected via USB or via RS-232, there must be one controller with address 1. It is not required that this controller is directly connected to the host PC, i.e. this controller does not have to be the first controller of the daisy-chain.

If there is no controller in a daisy-chain with address 1 an error message occurs when you try to setup a connection.

Wrong command or wrong syntax

⇒ Check the error code with the ERR? command (p. 127). "Error Codes" (p. 192) gives the complete error reference.

Wrong axis commanded

⇒ Check if the correct axis identifier is used and if the commanded axis is that of the desired stage (axis identifier also required with single-axis systems!)

Wrong controller parameter settings

⇒ Check the parameter settings with SPA? (p. 178) and SEP? (p. 174). See "Controller Parameters" (p. 35) for more information.

Custom software accessing PI drivers does not run.

Wrong combination of driver routines/VIs

⇒ Check if system runs with Terminal program. If yes read the software manual and compare sample code from the E-861 CD to check the necessary driver routines.

12 Customer Service

Call your PI representative or write to info@pi.ws; please have the following information about your system ready:

- Product codes and serial numbers of all products in the system
- Current firmware version of the controller (if present)
- Version of drivers and / or host software (if present)
- Operating system on host PC (if present)

13 Old Equipment Disposal

In accordance with EU directive 2002 / 96 / EC (WEEE), as of 13 August 2005, electrical and electronic equipment may not be disposed of in the member states of the EU mixed with other wastes.

To meet the manufacturer's product responsibility with regard to this product, Physik Instrumente (PI) GmbH & Co. KG will ensure environmentally correct disposal of old PI equipment that was first put into circulation after 13 August 2005, free of charge.

If you have such old equipment from PI, you can send it to the following address postage-free:

Physik Instrumente (PI) GmbH & Co. KG
Auf der Römerstr. 1
76228 Karlsruhe, Germany



14 Technical Data

14.1 Specifications

	E-861.1A1
Function	Controller for NEXACT® drives / systems
Drive type	NEXACT® linear drive
Channels	1
Motion and control	
Servo characteristics	P-I-D- amplifier, parameter change on-the-fly
Trajectory profile modes	Trapezoidal
Encoder input	Analog encoder input sine-cosine, interpolation circuit preset for differential transmission, 1 V _{pp} and 2.5 V offset of the encoder signal
Stall detection	Servo off, triggered by programmable position error
Input limit switch	2 x TTL (pull-up/pull-down, programmable)
Input reference switch	1 x TTL
Electrical properties	
Output power	max. 40 W
Output voltage	-10 to +45 V
Current consumption	max. 2 A
Interfaces and operation	
Communication interfaces	USB 1.0, RS-232 (9-pin (m) Sub-D)
Motor connector	Sub-D 15-pin (f) High Density
Sensor connector	Sub-D 15-pin (m) High Density
Controller network	Up to 16 units on single interface
I/O ports	4 analog/digital in, 4 digital out (TTL)
Command set	PI General Command Set (GCS)
User software	PIMikroMove, PI Terminal
Software drivers	GCS-DLL, LabVIEW drivers
Supported functionality	Start-up macro; data recorder for categories like current

	position or velocity; internal safety circuitry: watchdog timer
Manual control (optional)	Joystick, Y-cable for 2D motion, pushbutton box
Miscellaneous	
Operating voltage	24 V included: external power supply, 24 V, 2.5 A
Operating temperature range	0°C to +50°C
Mass	1.1 kg
Dimensions	206 x 130 x 66 mm (with mounting rails)

14.2 Mounting Hole Pattern

Dimensions in millimeters, decimal places separated by commas

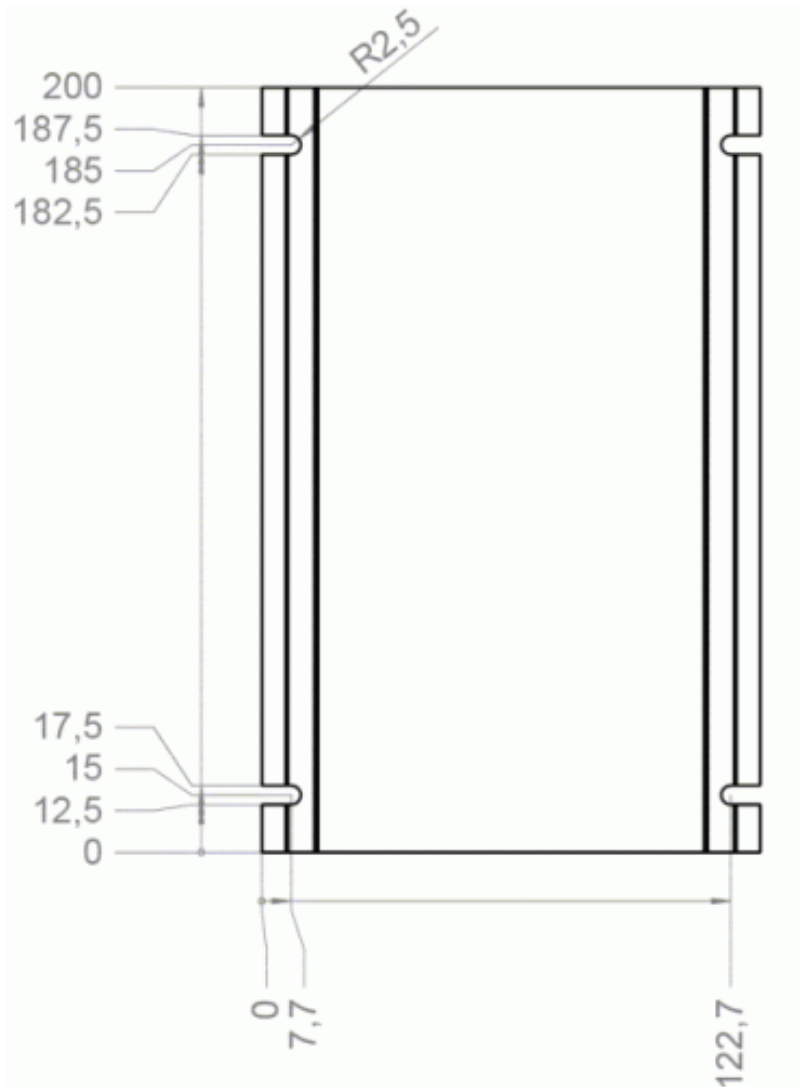


Figure 20: Bottom side of the E-861 case

14.3 Pin Assignments

14.3.1 Motor Socket

Connector type: Sub-D 15 (f), 3 row

Pin	Signal direction	Function
1	OUT	Piezo 1
2	OUT	Piezo 3
3	int. use	internal use
4	nc	nc
5	nc	nc
6	OUT	Piezo 0
7	OUT	Piezo 2
8	IN	AMP (amplifier enable)*
9	nc	nc
10	nc	nc
11	AGND	Piezo GND
12	AGND	Piezo GND
13	AGND	Piezo GND
14	GND	Digital GND
15	GND	Digital GND



*This pin is connected to GND in the connector shell of the NEXACT® drive to enable the amplifiers. If this connection is removed, all piezo voltages will be zero.

14.3.2 Sensor Socket

Connector type: Sub-D 15 (m), 3 row

Pin	Signal direction	Function
1	IN	REF (reference switch)
2	OUT	VDD (supply voltage encoder)
3	IN	REFP (positive reference trace from ruler*)
4	IN	COSP (positive cosine encoder signal)
5	IN	SINP (positive sine encoder signal)
6	IN	PLIMIT (positive limit switch)
7	IN	NLIMIT (negative limit switch)
8	IN	REFN (negative reference trace from ruler*)
9	IN	COSN (negative cosine encoder signal)
10	IN	SINN (negative sine encoder signal)
11	int. use	internal use
12	OUT	VDD (supply voltage limit board)
13	GND	Digital GND for reference and limit switches
14	AGND	Encoder signal GND
15	AGND	Encoder signal GND



* For the operation of the controller in closed-loop mode these signals are not obligatory.

14.3.3 RS-232 In and RS-232 Out Sockets

Connector Labels: RS-232 IN and RS-232 OUT
 Connector Types: Sub-D, 9-pin, male for OUT, female for IN

The RS-232 cable must never be connected to a PC at the same time an USB cable is connected.

The IN and OUT lines are permanently bussed together, straight-through. Only when the USB interface is active, does the controller assert signals on

the RxD (receive) line, pin 2, otherwise that line is driven by the host PC only. This is the reason an RS-232-only network may be limited to as few as 6 units.

Note that the controller RS-232 bus is wired as a DTE and, if connected to a PC, requires a cross-over (null-modem) cable.

Pin on all E-861 Connectors	Signal name on all E-861 Connectors*	Signal direction	Function
1			n.c.
2	RxD*	PC to controller**	Commands
3	TxD*	Controller** to PC	Reports (responses)
4			n.c.
5	GND		GND
6			n.c.
7			n.c.
8			n.c.
9			n.c.

*The RS-232 connection with the PC is via null-modem cable, so the connected signal names on the PC side are reversed.

** If the PC connection is via USB, then the E-861 connected to the PC copies everything received from the host over USB to the E-861 RxD line of *both* its RS-232 connectors. It also copies everything it sees on the E-861 TxD line to the host via USB.

14.3.4 USB Socket

Connector type: industry-standard USB Mini-B

When the USB interface is active, the controller asserts signals on the transmit line (TxD) of the RS-232 connectors for networking up to 15 further controllers. As a result the RS-232 cable must not be connected to the host PC when using USB.

14.3.5 I/O Socket

Connector type: Mini DIN 9-pin



Pin	Signal	Function	Identifier to use in GCS Commands (see below)
1	input	Input 1 (analog: 0 to +5V / digital: TTL)	1
2	input	Input 2 (analog: 0 to +5V / digital: TTL)	2
3	input	Input 3 (analog: 0 to +5V / digital: TTL)	3
4	input	Input 4 (analog: 0 to +5V / digital: TTL)	4
5	output	Output 1 (digital, TTL)	1
6	output	Output 2 (digital, TTL)	2
7	output	Output 3 (digital, TTL)	3
8	output	Output 4 (digital, TTL)	4
9	output	Vcc (+5V)	-

If the Input 1 to Input 4 lines are used as analog input lines:
 Their number is reported by the TAC? command (p. 185), their analog input values can be queried with the TAV? command (p. 185) and recorded using the record option 81 of the DRC command (p. 122).

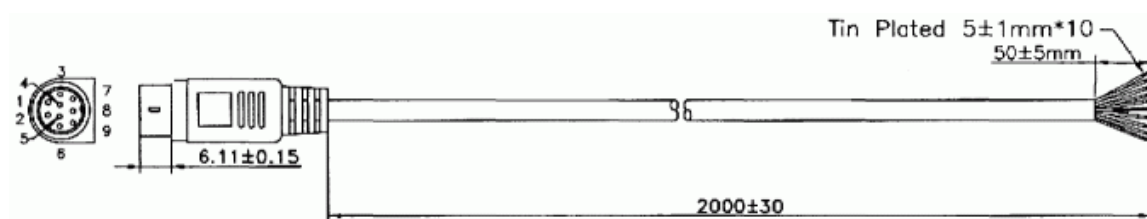
If the Input 1 to Input 4 lines are used as digital input lines:
 Their states (high/low) can be queried with the DIO? command (p. 121), the #4 command (p. 114) and the SRG? command (p. 178).

The states of the Output 1 to Output 4 lines (high/low) can be set using the DIO command (p. 121). Furthermore, you can program the Output 1 to

Output 4 lines using the CTO command (trigger configuration) and the TRO command (trigger enabling/disabling). See "Configuring Trigger Output—Examples" for examples.

14.3.6 C-170.IO Cable

The C-170.IO cable with open end is equipped with a Mini DIN 9-pin connector. You can use it to make the signals of the I/O socket (p. 218) available. This cable has to be ordered separately.



Specifications:

Temperature range: $-25\text{ }^{\circ}\text{C}$ to $+85\text{ }^{\circ}\text{C}$

Current rating: 1 A AC/DC

Insulation resistance: 50 M Ω min.

Voltage rating: 50 V AC/DC

Withstanding voltage: 500 V AC for 1 minute

Pin of Mini DIN 9-pin	Wire Color	Signal on I/O Socket of E-861
1	Black	Input 1 (analog: 0 to +5V / digital: TTL)
2	White	Input 2 (analog: 0 to +5V / digital: TTL)
3	Red	Input 3 (analog: 0 to +5V / digital: TTL)
4	Yellow	Input 4 (analog: 0 to +5V / digital: TTL)
5	Purple	Output 1 (digital, TTL)
6	Blue	Output 2 (digital, TTL)
7	Green	Output 3 (digital, TTL)
8	Brown	Output 4 (digital, TTL)

Pin of Mini DIN 9-pin	Wire Color	Signal on I/O Socket of E-861
9	Gray	Vcc (+5V)
Shell	Shield, black coated (thicker than the black wire connected to pin 1)	-

14.3.7 Joystick Socket

Connector type: Mini DIN 6-pin

Pin	Signal direction	Function	Identifier to use in GCS Commands (see below)
1		GND	-
2		n.c.	-
3	output	Vcc (3.3 V)	-
4	input	Input: Joystick Axis analog 0 to 3.3 V	1 for JAS? (p. 138), JAX (p. 139), JAX? (p. 140), JDT (p. 141), JLT (p. 142), JLT? (p. 143) 5 for DRC (p. 122)
5		n.c.	-
6	input	Input: Joystick Button #1	1 for JBS? (p. 140) 6 for DRC



The input values of the joystick axis and the joystick button can be recorded using the record option 81 of the DRC command.


14.3.8 Joystick Y-Cable

The joystick Y-cable (C-819.20Y) maps the signals of the second joystick axis (Y) and button to the first-axis inputs for the second controller.

Joystick Pin	Signal	Controller 1 Pin	Controller 2 Pin
1	GND	1	1
2	Button 2, 0 or 3.3 V		6
3	Vcc (3.3 V)	output	Vcc (3.3 V)
4	X-axis signal, 0 to 3.3 V	4	
5	Y-axis signal, 0 to 3.3 V		4
6	Button 1, 0 or 3.3 V	6	

14.3.9 24 V DC Socket

Connector type: barrel connector

Pin	Function	
Center	+24 VDC	



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