

STEP-200

2-axis stepping/servo motor control card

User Manual

Version 3.0 02/2001 Edition
Driver update : <http://www.icpdas.com>

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STEP200 2-axis Stepping/Servo Motor Control Card

STEP200 card is a 2-axis command-type stepping motor control card, it also can be used in servo motor control (pulse input type). This card has an embedded CPU which perform motion commands transfered from PC to increase the system performance. A 2Kbytes-FIFO is introduced as command buffer. This buffer can provide 1360ms buffer time. Therefore, STEP200 card is design for windows operation system. STEP200 card provide DOS, windows 95 and windows NT driver, let you have real time motion control solution in windows system.

Features

- 2-axis independent, simultaneous stepping motor control / servo motor control(pulse input type)
- step rate : 1pps~250Kpps
- Max. step count : $2^{32} - 1$ steps
- DOS, windows 95, windows NT driver
- embedded CPU
- command type interface
- linear, circular interpolation
- automatic trapezoidal acceleration / deceleration
- output pulse modes : CW/CCW or pulse / direction
- output polarity can be programmable
- 2500Vrms optical isolated signal output
- 5 optical isolated digital inputs per axis for limit switches

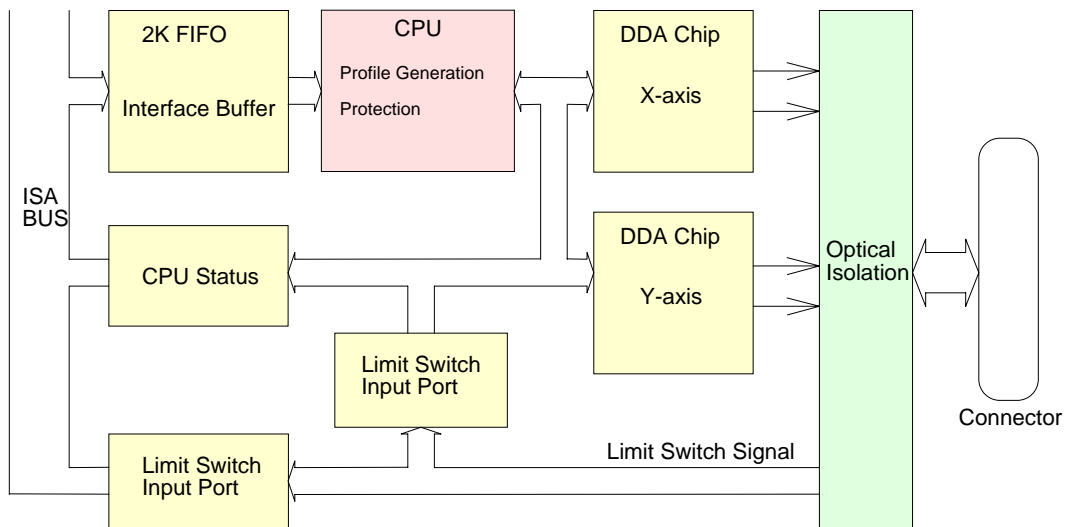
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1. Introduction

1.1 System Block Diagram

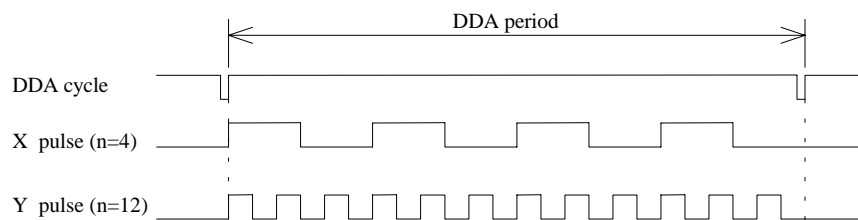
STEP200 Stepping motor control card is a micro-computer controlled, 2 axes pulse generation card. It includes a 2Kbytes-FIFO to receive motion command from host PC, a micro-computer for profile generation and protection, two axes DDA chip to execute DDA function when interpolation command is called, 2500Vrms optical isolation inserted for industrial application.



Figure(1) block diagram of STEP200

1.2 DDA Technology

The DDA chip is heart of STEP200 card, it will generate equal-space pulse train corresponding to specific pulse number during a DDA period. This mechanism is very useful to execute pulse generation and interpolation function. The DDA period can be determined by DDA cycle. Table(1) shows the relation among DDA cycle, DDA period and output pulse rate. When DDA cycle set to 1, the DDA period is equal to 8.192ms. The output pulse number can be set to 0~2047, therefore the maximum output pulse rate will be 249.877kpps. The minimum output pulse rate is 0.96pps when set DDA cycle=254 (DDA period = 1040.384ms).



Figure(2) DDA mechanism

Table(1) The Relation among DDA cycle, DDA period and output pulse rate.

DDA cycle	DDA period	Max. pulse rate(n=2047)	Min. pulse rate (n=1)
1	8.192ms	249877pps	122pps
2	12.288ms	166585pps	81pps
3	16.384ms	.	.
.	.	.	.
N	(N+1)*4.096ms	2047/(DDA period)	1/(DDA period)
.	.	.	.
254	1040.384ms	1967pps	0.96pps

The DDA cycle can be set by MSTEP2_SET_VAR(DDA_cycle, Acc_Dec, Low_Speed, High_Speed) command which described in chapter 3. The selection criterion of DDA cycle describes as following.

(1) The required max. output pulse rate.

$$PR_{max} = \frac{V_{max}}{60 * N}$$

$$PR_{max} = \frac{2047}{(DDA_{cycle} + 1) * 4.096ms}$$

PRmax : max. output pulse rate.

Vmax : max. speed (rpm).

N : the pulse number of stepping motor per revolution.
(pulse/rev).

2. The required speed resolution.

The maximum output pulse number is Np(0~2047), therefore the speed resolution is Vmax(max. speed)/Np. The DDA cycle can obtain as following.

$$PR_{max} = \frac{Np}{(DDA_{cycle} + 1) * 4.096ms}$$

3. Large DDA cycle (DDA period), it will occur vibration between different pulse input which generally can be observed during acceleration or deceleration. So, the small DDA cycle, the smooth acceleration/deceleration curve as long as the speed resolution can be acceptable.

Example: Stepping Motor

The specification of stepping motor is 500 pulse/rev, max. speed 500 rpm, speed resolution 2 rpm.

The required max. pulse rate

$$PR_{max} = 500 \text{ rpm}/60 * 500 = 4166.67 \text{ pps}$$

The maximum output pulse

$$N_p = 500\text{rpm}/2\text{rpm} = 250 \text{ pulse number}$$

The DDA cycle can be calculated by follow equation

$$PR_{max} = \frac{N_p}{(DDA_{cycle} + 1) * 4.096ms}$$

$$4166.67 = \frac{250}{(DDA_{cycle} + 1) * 4.096ms}$$

$$DDA \text{ cycle} = 14$$

$$\text{High Speed} = 256 \text{ pulse } (4166.67 * 15 * 0.004096)$$

The above results means that maximum speed is 500rpm when send command MSTEP2_SET_VAR(14, 1, 10, 256) to STEP200 card.

Example: Pulse type input Servo Motor

The specification of servo motor is 4000 pulse/rev, max. speed 3000 rpm, speed resolution 2 rpm.

The required max. pulse rate

$$PR_{max} = 3000 \text{ rpm}/60 * 4000 = 200,000 \text{ pps}$$

The maximum output pulse

$$N_p = 3000\text{rpm}/2\text{rpm} = 1500 \text{ pulse number}$$

The DDA cycle can be calculated by follow equation

$$PR_{max} = \frac{N_p}{(DDA_{cycle} + 1) * 4.096ms}$$

$$200,000 = \frac{1500}{(DDA_{cycle} + 1) * 4.096ms}$$

$$DDA \text{ cycle} = 1$$

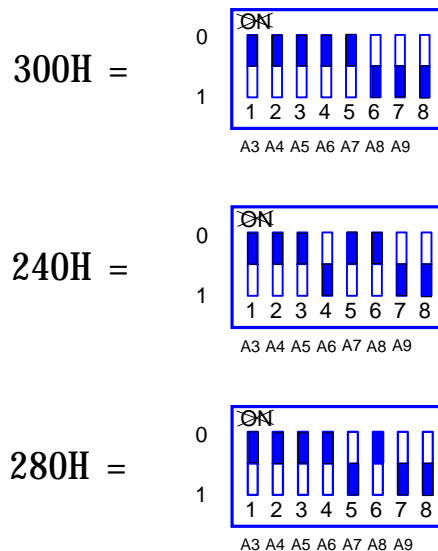
$$\text{High Speed} = 1638 \text{ pulse } (200,000 * 2 * 0.004096)$$

The above results means that maximum speed is 3000rpm when send command MSTEP2_SET_VAR(1, 5, 20, 1638) to STEP200 card.

2 Hardware setup

2.1 Address selection

The address is determined by A3~A9, there exist a dip switch on STEP200 card for address selection. The address can be select as following examples. Relatively, this address must be set using MSTEP2_REGISTRATION() command to select STEP200 card. The MSTEP2_REGISTRATION() command has been described in chapter 3.



Figure(3) Address selection

2.2 Register of STEP200 card

There are 4 registers which resided in selected address (base) on STEP200 card. It includes FIFO register, DI1 register, DI2 register, STS register.

(1) FIFO register (base + 0) (write only)

STEP200 driver will send motion command by way of this register. Please do not use this register to write any thing, or STEP200 will not operate properly.

(2) DI1 register (base + 0) (read only)

MSB 7	6	5	4	3	2	1	0 LSB
/EMG	xx	xx	/LS14	/LS13	/LS12	/LS11	/ORG1

/ORG1 : original point switch of X-axis, low active.

/LS11, /LS12, /LS13, /LS14 : limit switches of X-axis, low active, which must be configured as next session.

/EMG : emergency switch, low active.

(3) DI1 register (base + 1) (read only)

MSB 7	6	5	4	3	2	1	0 LSB
ystop	xstop	xx	/LS24	/LS23	/LS22	/LS21	/ORG2

/ORG2 : original point switch of Y-axis, low active.

/LS21, /LS22, /LS23, /LS24 : limit switches of Y-axis, low active, which must be configured as next session.

xstop, ystop : These signals indicate the operating situation of X, Y axis in CPU.

1 : busy, 0 : stop

The commands MSTEP2_WAIT_X() and MSTEP2_WAIT_Y() just to waiting for 'xstop' or 'ystop' signal become to '0'.

(4) STS register (base + 2) (read only)

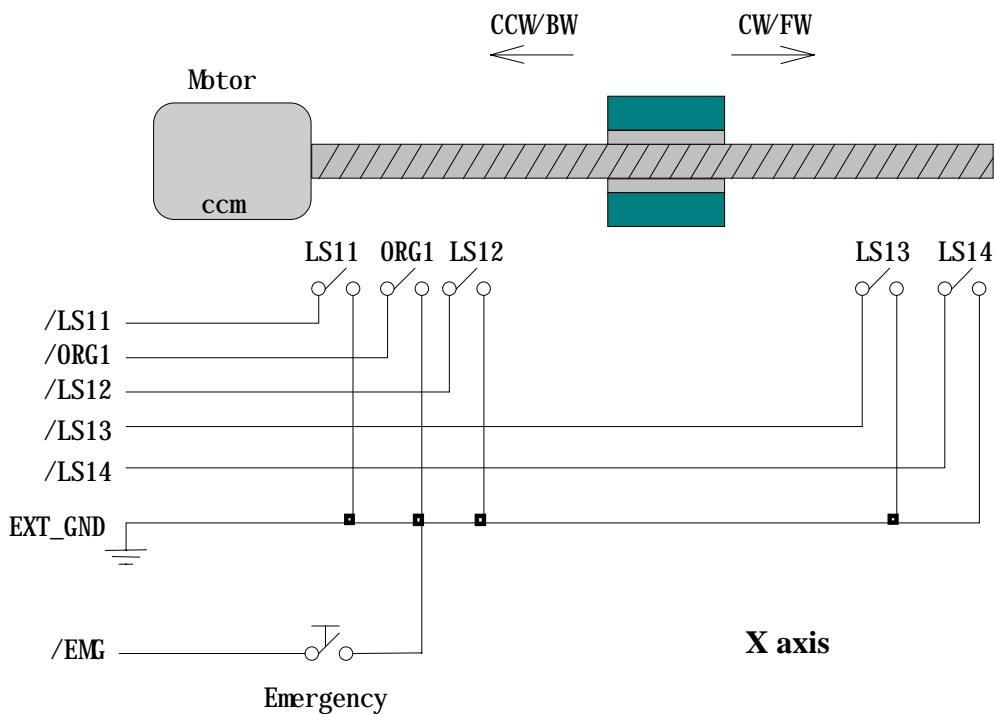
This register is used for manufacturing and testing.

2.3 Hardware Configuration

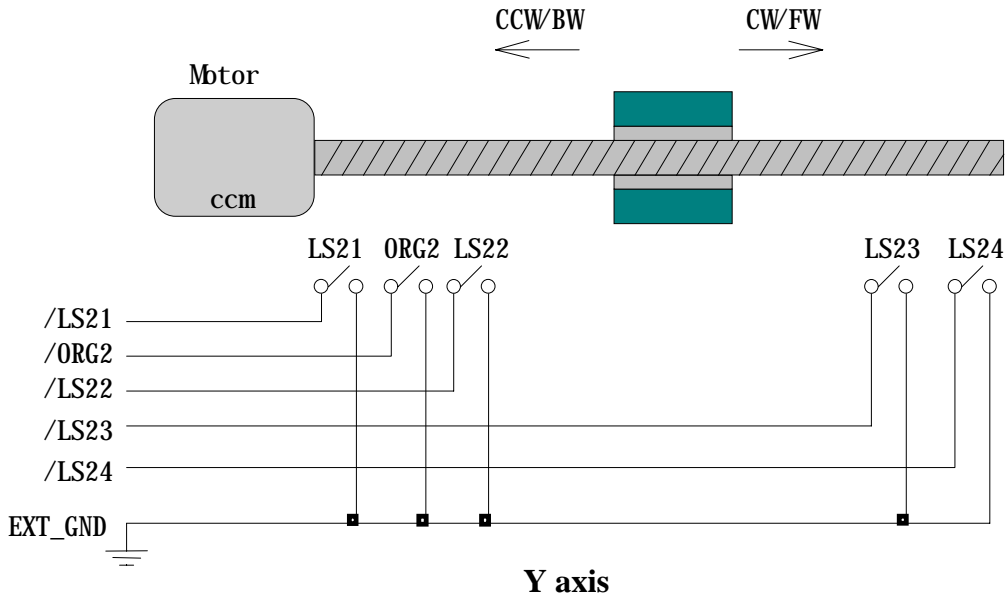
2.3.1 Limit switch configuration

Because the profile generation and protection is executed by the CPU on STEP200 card, the limit switches must configure as following diagram.

The motion command just can work properly.



Figure(4) Limit switch configuration of X axis



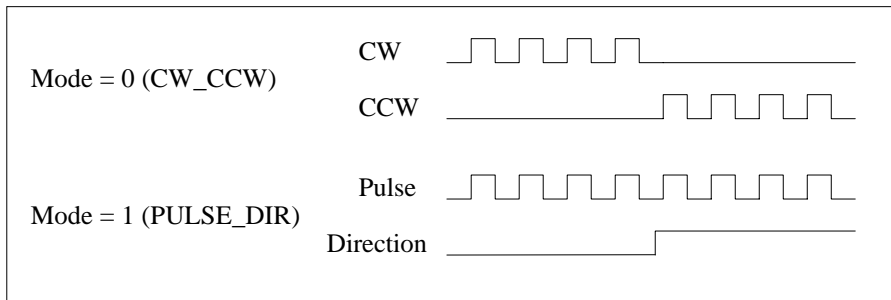
Figure(5) Limit switch configuration of Y axis

2.3.2 Output pulse mode configuration

STEP200 card provide two kind output method.

- (a) CW/CCW mode
- (b) Pulse/Direction mode

The command MSTEP2_SET_MODE(modeX, modeY) provide parameters CW_CCW (0) and PULSE_DIR (1) to define output pulse mode.



Figure(6) Output pulse mode

2.3.3 Direction configuration

Sometimes, the output direction of X-axis, Y-axis is undesired direction due to motor connection or gear train. In order to unify the output direction as shown in Figure(4) and Figure(5). Where CW/FW direction is defined as toward outside from motor, CCW/BW direction is defined as toward inside from motor. MSTEP2_SET_DEFDIR(defdirX, defdirY) command provide parameters NORMAL_DIR (0) and REVERSE_DIR (0) to define the rotating direction of motor.

2.3.4 Turn Servo ON/OFF (Hold ON/OFF)

To turn servo motor into servo ON(OFF) state, or turn stepping motor into hold ON(OFF) state, the command MSTEP2_SET_SERVO_ON(sonX, sonY) provide parameters ON (1) and OFF (0) to turn ON or OFF.

2.3.5 Protection

STEP200 card is a automatic protected system.

- (a) If X-axis command is executing and moving toward CW/FW direction, X-axis will immediately stop when LS14 is touched. To release this protection as long as X-axis move toward CCW/BW direction.
- (b) If X-axis command is executing and moving toward CCW/BW direction, X-axis will immediately stop when LS11 is touched. To release this protection as long as X-axis move toward CW/FW direction.
- (c) If Y-axis command is executing and moving toward CW/FW direction, Y-axis will immediately stop when LS24 is touched. To release this protection as long as Y-axis move toward CCW/BW direction.
- (d) If Y-axis command is executing and moving toward CCW/BW direction, Y-axis will immediately stop when LS21 is touched. To release this protection, as long as Y-axis move toward CW/FW direction.

2.4 Connection

(1) Pin Assignment of connector CN1

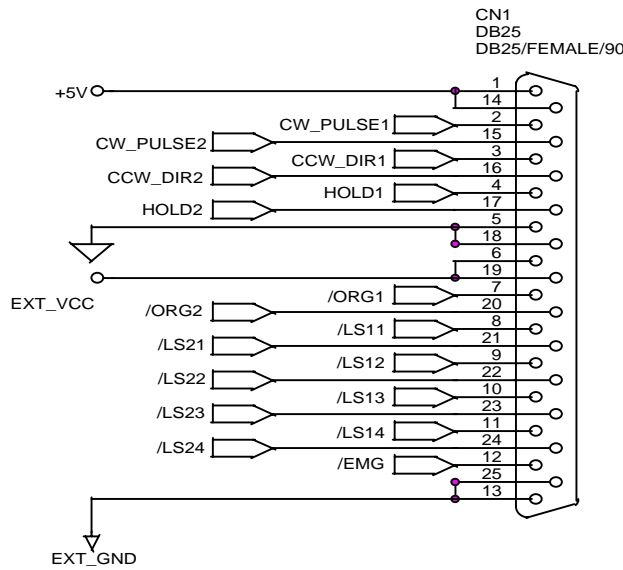


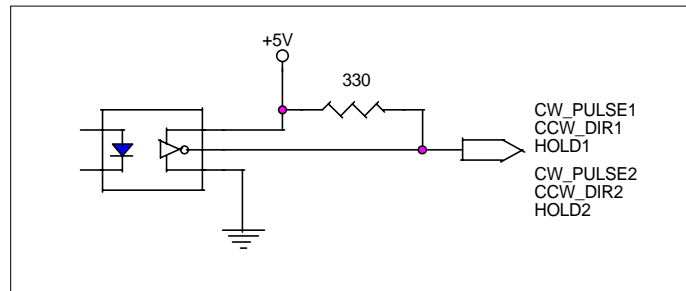
Figure (7) CN1 connector

Table(2)

pin name	which axis	
CW_PULSE1	X	can be configure as CW or PULSE pin
CCW_DIR1	X	can be configure as CCW or DIR pin
HOLD1	X	servo ON/OFF or hold ON/OFF signal 1: ON, 0: OFF
CW_PULSE2	Y	can be configure as CW or PULSE pin
CCW_DIR2	Y	can be configure as CCW or DIR pin
HOLD2	Y	servo ON/OFF or hold ON/OFF signal 1: ON, 0: OFF
/ORG1, /LS11, /LS12 /LS13, /LS14	X	original point ,limit switches, low active should be configure as Figure(4)
/ORG2, /LS21, /LS22 /LS23, /LS24	Y	original point, limit switches, low active should be configure as Figure(5)
/EMG		emergency switch, low active
+5V pin 1 pin 14		internal supplied voltage, only used for output pulse. (50mA) don't use for other device
GND pin 5 pin 18		internal ground, only used for output pulse. don't use for other device
EXT_VCC pin 6 pin 19		external power 12V~24V, used for limit switches
EXT_GND pin 13 pin 25		external ground, used for limit switches

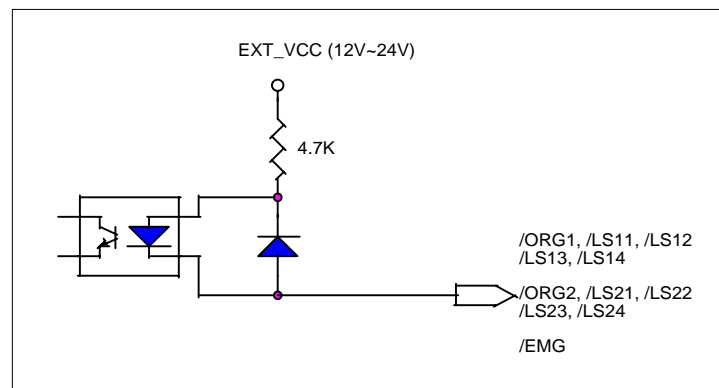
(2) The internal circuit of CW_PULSE, CCW_DIR, HOLD

When output these signal as 1, it can source 15mA(max.).
 When output these signal as 0, it can sink 50mA(max.)



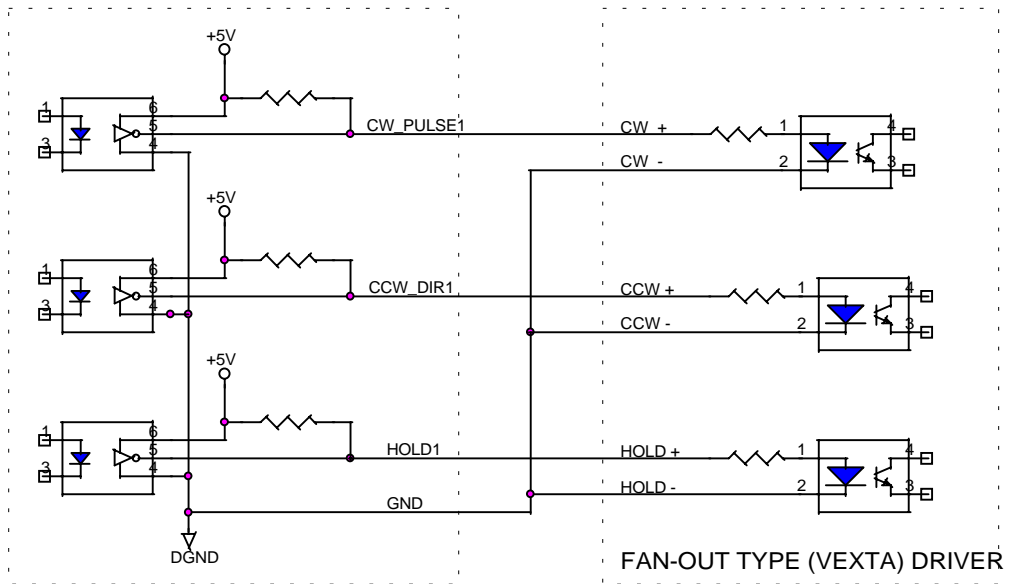
Figure(8) internal signal of pulse output connection

(3) The internal circuit of switch connection

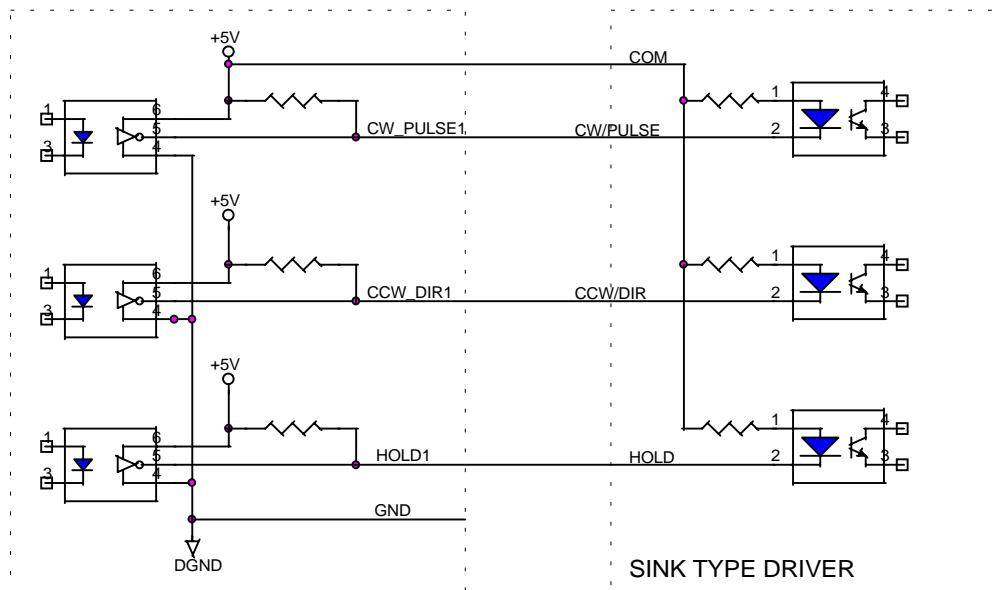


Figure(9) internal circuit of limit switch connection

(3) Examples for connection



Figure(10) fan-out type driver (VEXTA's motor driver)



Figure(11) Sink type driver

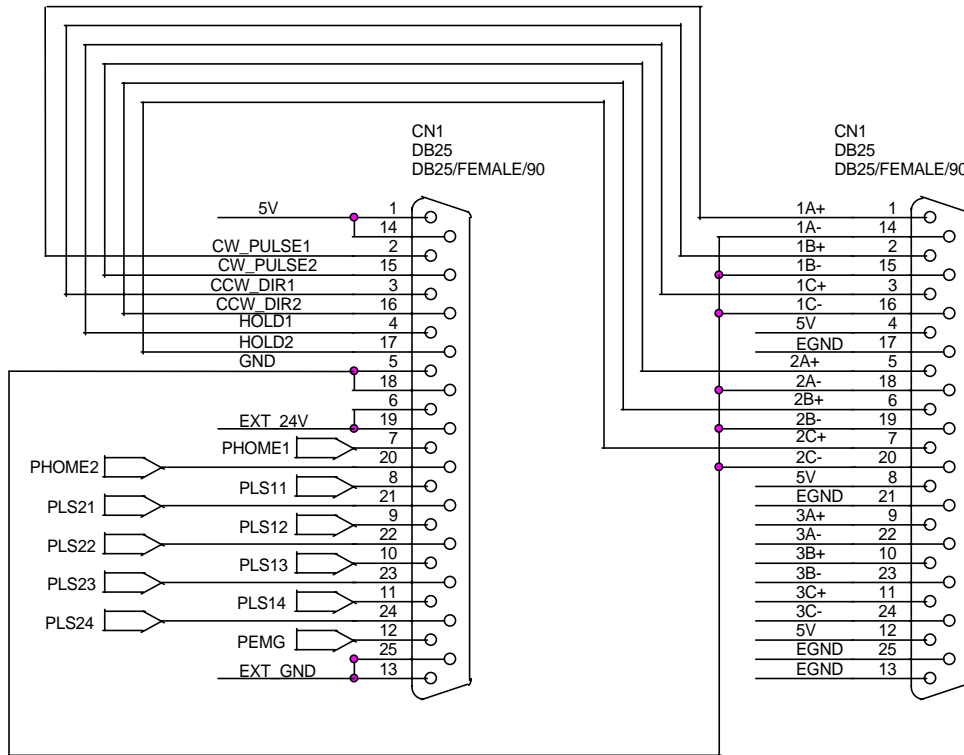
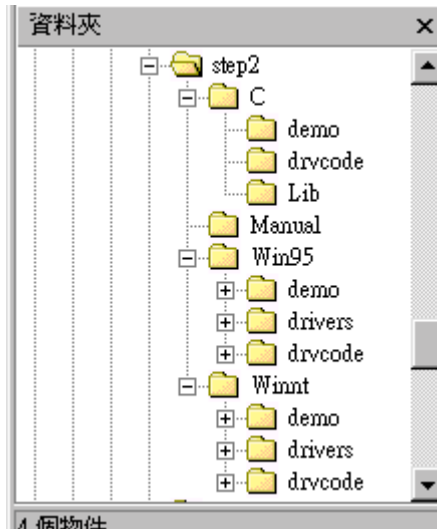


Figure (12) The connection between ENCODER3 card and STEP200 card.(for testing)

3. Software

Directories



3.1 Functions

Constants

```
#define ON          1
#define OFF         0
#define CW_CCW     0
#define PULSE_DIR  1
#define NORMAL_DIR 0
#define REVERSE_DIR 1
#define FW         0
#define BW         1
#define CW         0
#define CCW        1
#define X_axis     1
#define Y_axis     2
#define READY 0
#define BUSY 1
```

STEP200 card is a automatic protected system.

- (a) If X-axis command is executing and moving toward CW/FW direction, X-axis will immediately stop when LS14 is touched. To release this protection as long as X-axis move toward CCW/BW direction.
- (b) If X-axis command is executing and moving toward CCW/BW direction, X-axis will immediately stop when LS11 is touched. To release this protection as long as X-axis move toward CW/FW direction.
- (c) If Y-axis command is executing and moving toward CW/FW direction, Y-axis will immediately stop when LS24 is touched. To release this

protection as long as Y-axis move toward CCW/BW direction.

- (d) If Y-axis command is executing and moving toward CCW/BW direction, Y-axis will immediately stop when LS21 is touched. To release this protection, as long as Y-axis move toward CW/FW direction.

3.1.1 Loading and unloading driver commands (only for windows)

(1) MSTEP2_INITIAL()

To load VxD driver.

(2) MSTEP2_END()

To release VxD driver.

3.1.2 Setting commands

(3) unsigned char MSTEP2_REGISTRATION(unsigned char cardNo, unsigned int address);

To select the address of board and check it exist or not. 20 STEP-200 boards can be added in one system.

cardNo : board number 0~19.

address : select the address as well as hardware selected in chapter 2.

return NO : board not exist

YES : board exist

Example:

```
MSTEP2_REGISTRATION(1, 0x300);
```

(4) MSTEP2_RESET_SYSTEM(unsigned char cardNo)

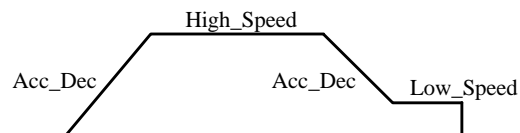
to reset STEP-200 card.

cardNo : board number 0~19.

(5) MSTEP2_SET_VAR(unsigned char cardNo, unsigned char DDA_cycle, unsigned char Acc_Dec, unsigned int Low_Speed, unsigned int High_Speed)

to set variable of DDA cycle, accelerating/decelerating speed, low speed and high speed value.

cardNo : board number 0~19.



Restriction:

$$1 \leq DDA_cycle \leq 254$$

$$1 \leq Acc_Dec \leq 200$$

$$1 \leq Low_Speed \leq 200$$

$$Low_Speed \leq High_Speed \leq 2047$$

default value

$$DDA_cycle = 10$$

$$Acc_Dec = 1$$

$$Low_Speed = 10$$

$$High_Speed = 100$$

Example:

```
MSTEP2_SET_VAR(1, 5, 2, 10, 150);
```

where

```
DDA_cycle = 5 --> DDA period = (5+1)*4.096ms = 24.576ms
Acc_Dec = 2 --> Acc/Dec speed = 2/(24.576ms)^2 = 3311 p/s^2
Low_Speed = 10 --> low speed = 10/24.576ms = 407pps
High_Speed = 150 --> high speed = 150/24.576ms = 6107pps
```

**(6) MSTEP2_SET_DEFDIR(unsigned char cardNo,
unsigned char defdirX,
unsigned char defdirY)**

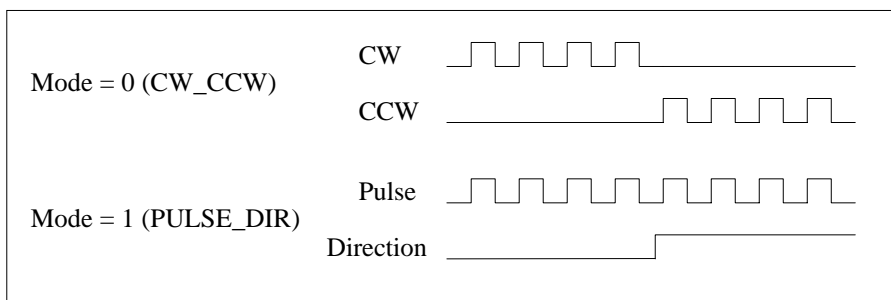
Sometimes, the output direction of X-axis, Y-axis is undesired direction due to motor connection or gear train. In order to unify the output direction as shown in Figure(4) and Figure(5). Where CW/FW direction is defined as toward outside from motor, CCW/BW direction is defined as toward inside from motor. MSTEP2_SET_DEFDIR() command provide parameters to define the rotating direction of motor.

```
cardNo : board number 0~19.
defdirX : X axis direction definition
defdirY : Y axis direction definition
0 : NORMAL_DIR
1 : REVERSE_DIR
```

**(7) MSTEP2_SET_MODE(unsigned char cardNo,
unsigned char modeX,
unsigned char modeY)**

STEP200 card provide two kind output method.

```
modeX : X axis output mode
modeY : Y axis output mode
0 : CW_CCW CW/CCW mode
1 : PULSE_DIR Pulse/Direction mode
```



Example:

```
MSTEP2_SET_MODE(1,CW_CCW, PULSE_DIR);
```

**(8) MSTEP2_SET_SERVO_ON(unsigned char cardNo,
unsigned char sonX, unsigned char sonY)**

To turn servo motor into servo ON(OFF) state, or turn stepping motor into

hold ON(OFF) state.

sonX : X axis servo/hold on switch

sonY : Y axis servo/hold on switch

1 : ON

0 : OFF

3.1.3 Stop Commands

(9) MSTEP2_STOP_X(unsigned char cardNo)

to stop X axis.

(10) MSTEP2_STOP_Y(unsigned char cardNo)

to stop Y axis.

(11) MSTEP2_STOP_ALL(unsigned char cardNo)

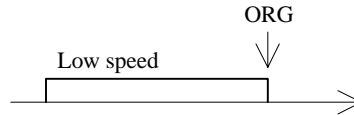
to stop X, Y axis immediatly.

This command will clear commands pending the FIFO, and then send stop X, Y axis command to achieve immediately stop all axis.

3.1.4 Simple motion commands

(12) MSTEP2_LSP_ORG(unsigned char cardNo, unsigned char DIR, unsigned char AXIS)

Low speed move , and stop when **ORG1/ORG2** limit switch is touched.

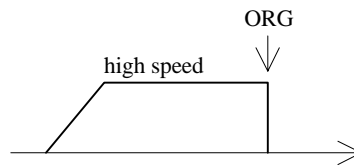


Example:

```
MSTEP2_LSP_ORG(1, CCW, X_axis);
MSTEP2_LSP_ORG(1, CCW, Y_axis);
```

(13) MSTEP2_HSP_ORG(unsigned char cardNo, unsigned char DIR, unsigned char AXIS)

High speed move , and stop when **ORG1/ORG2** limit switch is touched.

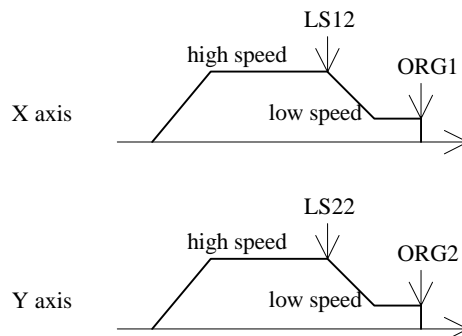


Example:

```
MSTEP2_HSP_ORG(1, CCW, X_axis);
MSTEP2_HSP_ORG(1, CCW, Y_axis);
```

(14) MSTEP2_HSD_ORG(unsigned char cardNo, unsigned char DIR, unsigned char AXIS)

High speed move , and slow down to low speed when **LS12/LS22** limit switch is touched, and then stop when reach **ORG1/ORG2** limit switch.



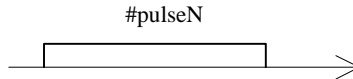
Example:

```
MSTEP2_HSD_ORG(1, CCW, X_axis);
```

MSTEP2_HSD_ORG(1, CCW, Y_axis);

**(15) MSTEP2_LSP_PULSE_MOVE(unsigned char cardNo,
unsigned char AXIS, long pulseN)**

Low speed move #pulseN



Example:

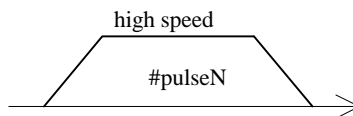
```
MSTEP2_LSP_PULSE_MOVE(1, X_axis, 20000);
MSTEP2_LSP_PULSE_MOVE(1, X_axis, -2000);
MSTEP2_LSP_PULSE_MOVE(1, Y_axis, 20000);
MSTEP2_LSP_PULSE_MOVE(1, Y_axis, -2000);
```

where

when pulseN>0, move toward CW/FW direction
when pulseN<0, move toward CCW/BW direction

**(16) MSTEP2_HSP_PULSE_MOVE(unsigned char cardNo,
unsigned char AXIS, long pulseN)**

High speed move #pulseN.



Example:

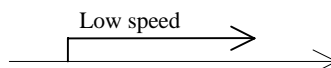
```
MSTEP2_HSP_PULSE_MOVE(1, X_axis, 20000);
MSTEP2_HSP_PULSE_MOVE(1, X_axis, -2000);
MSTEP2_HSP_PULSE_MOVE(1, Y_axis, 20000);
MSTEP2_HSP_PULSE_MOVE(1, Y_axis, -2000);
```

where

when pulseN>0, move toward CW/FW direction
when pulseN<0, move toward CCW/BW direction

**(17) MSTEP2_LSP_MOVE(unsigned char cardNo,
unsigned char DIR, unsigned char AXIS)**

Low speed move toward direction DIR. It can be stop by MSTEP2_STOP_X or MSTEP2_STOP_Y or MSTEP2_STOP_ALL command.



Example:

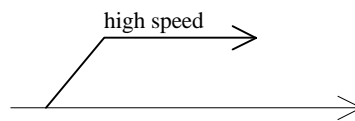
```

MSTEP2_LSP_MOVE(1, CW, X_axis);
getch( );
MSTEP2_STOP_X(1);
MSTEP2_LSP_MOVE(1, CCW, Y_axis);
getch( );
MSTEP2_STOP_Y(1);

```

**(18) MSTEP2_HSP_MOVE(unsigned char cardNo,
unsigned char DIR, unsigned char AXIS)**

High speed move toward direction DIR. It can be stop by MSTEP2_STOP_X or MSTEP2_STOP_Y or MSTEP2_STOP_ALL command.



Example:

```

MSTEP2_HSP_MOVE(1, CW, X_axis);
getch( );
MSTEP2_STOP_X(1);
MSTEP2_HSP_MOVE(1, CCW, Y_axis);
getch( );
MSTEP2_STOP_Y(1);

```

**(19) MSTEP2_CSP_MOVE(unsigned char cardNo, unsigned char dir,
unsigned char axis, unsigned int move_speed)**

This command will accelerate/decelerate the selected axis's motor to the "move_speed". This command can be continuously send to STEP-200 to dynamicly change speed. The rotating motor can be stop by the command MSTEP2_STOP() or MSTEP2_DEC_STOP().

cardNo : board number 0~9.

axis : selected axis.

1 : X axis

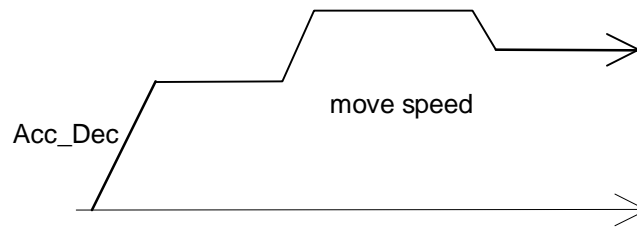
2 : Y axis

dir : moving direction.

0 : CW

1 : CCW

0 < move_speed <= 2040

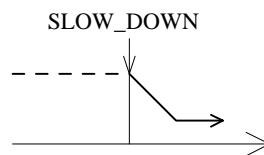


Example:

```
MSTEP2_CSP_MOVE(1, CW, X_axis, 10);
delay(10000);
MSTEP2_CSP_MOVE(1, CW, X_axis, 20);
delay(10000);
MSTEP2_CSP_MOVE(1, CW, X_axis, 30);
delay(10000);
```

(20) MSTEP2_SLOW_DOWN(unsigned char cardNo, unsigned char AXIS)

to decelerate to slow speed until MSTEP2_STOP_X() or MSTEP2_STOP_Y or MSTEP2_STOP_ALL is executed.

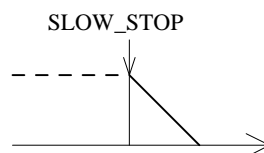


Example:

```
MSTEP2_HSP_MOVE(1, CW, X_axis);
getch( );
MSTEP2_SLOW_DOWN(1, X_axis);
getch( );
MSTEP2_STOP_X(1);
```

(21) MSTEP2_SLOW_STOP(unsigned char cardNo, unsigned char AXIS)

to decelerate to stop.



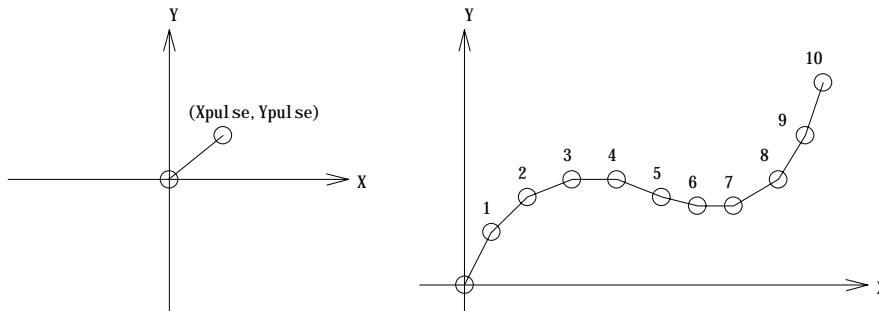
Example:

```
MSTEP2_HSP_MOVE(1, CW, Y_axis);
getch( );
MSTEP2_SLOW_STOP(1, Y_axis);
```

3.1.5 Interpolation commands

(22) MSTEP2_INTP_PULSE(unsigned char cardNo, int Xpulse, int Ypulse)

This command will move a short distance(interpolation short line) in X-Y plane. This command provide user to generate an arbitrary curve in X-Y plane.



Restriction:

$$-2047 \leq \# Xpulse \leq 2047$$

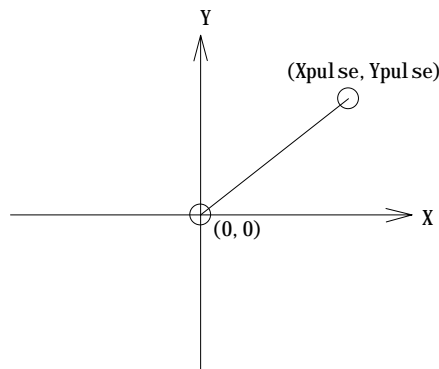
$$-2047 \leq \# Ypulse \leq 2047$$

Example:

```
MSTEP2_INTP_PULSE(1,20,20);
MSTEP2_INTP_PULSE(1,20,13);
MSTEP2_INTP_PULSE(1,20,7);
MSTEP2_INTP_PULSE(1,20,0);
MSTEP2_INTP_PULSE(1,15,-5);
```

(23) MSTEP2_INTP_LINE(unsigned char cardNo, long Xpulse, long Ypulse)

This command will move a long distance(interpolation line) in X-Y plane. The CPU on STEP200 card will generate a trapezoidal speed profile of X-axis and Y-axis, and execute interpolation by way of DDA chip.



Restriction:

$$-524287 \leq \#Xpulse \leq 524287$$

$$-524287 \leq \#Ypulse \leq 524287$$

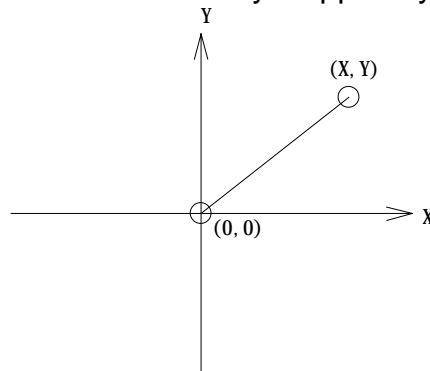
Example:

```
MSTEP2_INTP_LINE(1,2000,-3000);
```

```
MSTEP2_INTP_LINE(1,-500,200);
```

(24) MSTEP2_INTP_LONG_LINE(unsigned char cardNo, long x, long y, unsigned int speed)

This command will move a long interpolation line in X-Y plane. PC will automatically generate a trapezoidal speed profile of X-axis and Y-axis, and send these profile by way of MSTEP2_INTP_PULSE() command. This command only can be immediately stopped by /EMG switch.



speed : 0~2040

Restriction:

$$-2^{32} + 1 \leq \#x \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq \#y \leq 2^{32} - 1$$

Example:

```
MSTEP2_INTP_LONG_LINE(1,20000,-30000);
```

(25) MSTEP2_CIRCLE(unsigned char cardNo, long x, long y, unsigned char dir, unsigned int speed)

This command will generate a interpolation circle in X-Y plane. PC will automatically generate a trapezoidal speed profile of X-axis and Y-axis, and send these profile by way of MSTEP2_INTP_PULSE() command. This command only can be immediately stopped by /EMG switch.

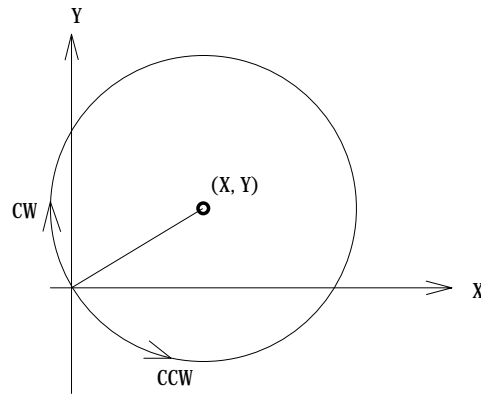
x, y : center point of circle relate to present position.

dir : moving direction.

0 : CW

1 : CCW

speed : 0~2040



where radius = $\sqrt{X^2 + Y^2}$

Restriction:

$$-2^{32} + 1 \leq x \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq y \leq 2^{32} - 1$$

Example:

```
MSTEP2_INTP_CIRCLE(1,2000,-2000,CW,100);
```

(26) MSTEP2_ARC(unsigned char cardNo, long x, long y, long R, unsigned char dir, unsigned int speed)

This command will generate a interpolation arc in X-Y plane. PC will automatically generate a trapezoidal speed profile of X-axis and Y-axis, and send these profile by way of MSTEP2_INTP_PULSE() command. This command only can be immediately stopped by /EMG switch.

x, y : end point of arc relate to present position.

R : radius of arc.

if $R > 0$, the arc < 180 degree

if $R < 0$, the arc > 180 degree

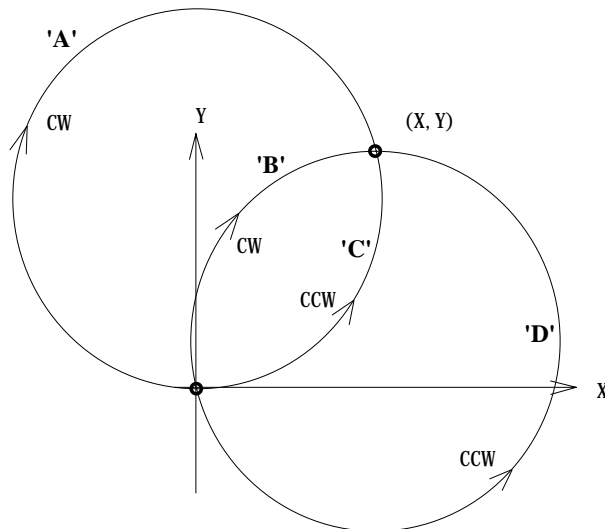
dir : moving direction.

0 : CW

1 : CCW

R	dir	path of curve
$R > 0$	CW	'B'
$R > 0$	CCW	'C'
$R < 0$	CW	'A'
$R < 0$	CCW	'D'

speed : 0~2040



Restriction:

$$-2^{32} + 1 \leq \#x \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq \#y \leq 2^{32} - 1$$

$$-2^{32} + 1 \leq \#R \leq 2^{32} - 1$$

$$R \geq \frac{\sqrt{x^2 + y^2}}{2}$$

Example:

MSTEP2_INTP_ARC(1,2000,-2000,2000,CW,100);

3.1.6 Others

(27) unsigned char MSTEP2_LIMIT_X(unsigned char cardNo)

to request the condition of X-axis limit switches

MSB 7	6	5	4	3	2	1	0 LSB
/EMG	xx	xx	/LS14	/LS13	/LS12	/LS11	/ORG1

/ORG1 : original point switch of X-axis, low active.

/LS11, /LS12, /LS13, /LS14 : limit switches of X-axis, low active, which must be configured as Figure(4).

/EMG : emergency switch, low active.

Example:

```
unsigned char limit1;
limit1 = MSTEP2_LIMIT_X(1);
```

(28) unsigned char MSTEP2_LIMIT_Y(unsigned char cardNo)

to request the condition of Y-axis limit switches

MSB 7	6	5	4	3	2	1	0 LSB
ystop	xstop	xx	/LS24	/LS23	/LS22	/LS21	/ORG2

/ORG2 : original point switch of Y-axis, low active.

/LS21, /LS22, /LS23, /LS24 : limit switches of Y-axis, low active, which must be configured as Figure(5).

Example:

```
limit2 = MSTEP2_LIMIT_Y(1);
```

(29) MSTEP2_WAIT_X(unsigned char cardNo)

to wait X-axis going to STOP state.

(30) MSTEP2_WAIT_Y(unsigned char cardNo)

to wait Y-axis going to STOP state.

3.1.7 New Commands

(31) MSTEP2_SET_NC(unsigned char cardNo, unsigned char sw);

To set all of the following limit switches as N.C.(normal close) or N.O.(normal open). If set as N.O., those limit switches are active low. If set as N.C., those limit switches are active high. The auto-protection will automatically change the judgement whatever it is N.O. or N.C..

Limit switches: ORG1, LS11, LS12, LS13, LS14, ORG2, LS21, LS22, LS23, LS24, EMG.

cardNo : card number 0~9.

sw: 0(NO) normal open (default).

1(YES) normal close.

(32) MSTEP2_EMG_STOP(unsigned char cardNo);

This function is the same as MSTEP2_STOP_ALL(), but MSTEP2_EMG_STOP() only can be used in timer interrupt routine.

cardNo : card number 0~9.

This command will clear all of pending commands in the buffer, and immediately terminate all commands which is executing in STEP-200 board.

(33) MSTEP2_INTP_LINE02(unsigned char cardNo, long x, long y, unsigned int speed, unsigned char acc_mode)

(34) MSTEP2_INTP_CIRCLE02(unsigned char cardNo, long x, long y, unsigned char dir, unsigned int speed, unsigned char acc_mode)

(35) MSTEP2_INTP_ARC02(unsigned char cardNo, long x, long y, long R, unsigned char dir, unsigned int speed, unsigned char acc_mode)

acc_mode: 0: enable acceleration and deceleration profile

1: disable acceleration and deceleration profile

The new driver provide a set of state-machine-type interpolation command including:

MSTEP2_INTP_LINE02

MSTEP2_INTP_CIRCLE02

MSTEP2_INTP_ARC02

These command can be set acc_mode=1 to disable the acceleration and

deceleration profile.

(36) unsigned char MSTEP2_INTP_STOP()

This command is to compute the interpolation service. It will return READY(0) for interpolation command completed. And return BUSY(1) for not yet complete.

(37) unsigned char MSTEP2_GET_CARD()

This command is used only for DOS in timer interrupt service (10ms) to compute the state-machine-type interpolation command.

These 3 state-machine-type interpolation commands must use **MSTEP2_GET_CARD()** (only for windows) and **MSTEP2_INTP_STOP()** simultaneously. The state-machine-type interpolation commands are only set parameters into the driver. The computing entity is in **MSTEP2_GET_CARD()** (only for windows) and **MSTEP2_INTP_STOP()**.

In windows application, when The MSTEP2_GET_CARD() command is running in the timer interrupt routine by 10ms, it will help to calculate the interpolation service.

Both of DOS and windows application, User can directly call the **do { while (MSTEP2_INTP_STOP()!=READY)** to execute the computing entity. The user can monitor something or waiting for keyboard input in the do loop. Therefore, The user has chance to do the software stop or monitor something.

DOS application example1

```
MSTEP2_INTP_LINE02(CARD1,1000,1000,100,1);
do
{
    show_panel();
    if (kbhit()) chkey=bioskey(0); //F7=0x4100
} while ( (chkey!= 0x4100) && (MSTEP2_INTP_STOP()!=READY) );
if (chkey==0x4100) MSTEP2_STOP_ALL(CARD1);
```

DOS application example2

```
void TimerInterrupt(void)
{
    MSTEP2_GET_CARD(CARD1);
    show_panel();
    if (kbhit()) chkey=bioskey(0); //F7=0x4100
```



```

}
void test_intp(void)
{
    MSTEP2_INTP_LINE02(CARD1,1000,1000,100,1);
    do
    { } while ( (chkey!= 0x4100) && (MSTEP2_INTP_STOP()!=READY) );
    if (chkey==0x4100) MSTEP2_STOP_ALL(CARD1);
}

```

Windows application example1

```

void __fastcall TMSERVO::Timer1Timer(TObject *Sender)

```

```

{
    Timer1->Interval = 10; //10ms
    MSTEP2_GET_CARD(CARD1);
    show_panel();
}

```

```

void __fastcall TMSTEP::IntpCircleClick(TObject *Sender)

```

```

{
char str[20];

if ( (MSTEP2_IS_X_STOP(CARD1)==NO)
    || (MSTEP2_IS_Y_STOP(CARD1)==NO)
    )
{
    Application->MessageBox(
        "Motor's rotating, can't execute this command",
        "Message Box",
        MB_DEFBUTTON1);
    return;
};

ltoa(x, str, 10);
IntpCircleDialog->Xcenter->Text = AnsiString(str);
ltoa(y, str, 10);
IntpCircleDialog->Ycenter->Text = AnsiString(str);
IntpCircleDialog->SelectDir->ItemIndex = direction;
ltoa(speed, str, 10);

```

```
IntpCircleDialog->speed->Text = AnsiString(str);

if (IntpCircleDialog->ShowModal()==mrOk)
{
  x= (long)IntpCircleDialog->Xcenter->Text.ToInt();
  y= (long)IntpCircleDialog->Ycenter->Text.ToInt();
  direction = IntpCircleDialog->SelectDir->ItemIndex;
  speed= (unsigned int)IntpCircleDialog->speed->Text.ToInt();
  //MSTEP2_CIRCLE(CARD1,x, y, (unsigned char)direction, speed);
  MSTEP2_INTP_CIRCLE02(CARD1,x,y,(unsigned char)direction,speed,0);
  do {Application->ProcessMessages();}
  while (MSTEP2_INTP_STOP()!=READY);
}
}
```

3.2 Start up and end of program

Start up program

When you are going to use STEP200 card, there are some commands must be used firstly.

MSTEP2_INITIAL()

to load vxd driver. DOS application don't need execute this command.

MSTEP2_REGISTRATION(CARD1,0x300)

set CARD1 address, (where CARD1=1)

MSTEP2_RESET_SYSTEM(CARD1);

reset system

MSTEP2_SET_VAR(CARD1, DDA, AD, LSP, HSP);

set DDA cycle, accelerating/decelerating speed, low speed and high speed value

MSTEP2_SET_DEFDIR(CARD1, xdir, ydir);

define direction.

MSTEP2_SET_MODE(CARD1, xmode, ymode);

define output mode.

MSTEP2_SET_SERVO_ON(CARD1, xson, yson);

set servo ON/OFF.

end of program

MSTEP2_RESET_SYSTEM(CARD1);

reset system

MSTEP2_END();

to release VxD driver. DOS application don't need execute this command.

Example

```
//-----
#define CARD1 1
unsigned char DDA,AD;
unsigned int LSP,HSP;
unsigned char xmode,ymode;
unsigned char xdir,ydir;
unsigned char xson,yson;

void main ()
{
    DDA = 5;
    AD = 5;
    LSP = 10;
    HSP = 120;
    xmode = CW_CCW;
    ymode = CW_CCW;
```

```
xdir = NORMAL_DIR;
ydir = NORMAL_DIR;
xson = ON;
yson = ON;

//--- start up program -----
MSTEP2_INITIAL();          //-- only used for windows application
MSTEP2_REGISTRATION(CARD1, 0x300);
MSTEP2_RESET_SYSTEM(CARD1);
MSTEP2_SET_VAR(CARD1, DDA, AD, LSP, HSP);
MSTEP2_SET_DEFDIR(CARD1, xdir, ydir);
MSTEP2_SET_MODE(CARD1, xmode, ymode);
MSTEP2_SET_SERVO_ON(CARD1, xson, yson);
.
.
.
//--- end of program -----
MSTEP2_RESET_SYSTEM(CARD1);
MSTEP2_END();             //-- only used for windows application
}
```

4. Driver

DOS Driver (C, C++)

Item	File
Header file	mstep2.h
Library file	mstep2.lib
Example file	mtest.prj

Windows 95 Driver

Item	File
Header file	step32.h
ImportLibrary file	step32.lib bcstep32.lib (only for Borland C++ series)
Dynamic Link Library	step32.dll(copy to c:\windows)
VxD file	vportd.vxd(copy to c:\windows)
Example file	project1.bpr(Borland C++ Builder) project1.cpp bbsetp.cpp

Windows NT Driver

Item	File
Header file	step32.h
Import Library file	step32.lib bcstep32.lib (only for Borland C++ series)
Dynamic Link Library	step32.dll(copy to c:\winnt)
Driver	regdrv.bat napwnt.ini napwnt.sys regini.exe
Example file	project1.bpr(Borland C++ Builder) project1.cpp bbsetp.cpp

The procedure of install NT drivers, to execute **regdrv.bat** and then re-start computer. The detail of installation, please refer regdrv.bat

5. Example

5.1 DOS example

The execution file MTEST.EXE is a command testing program, let you can fully understand the action of every command. The source files include MTEST.PRJ, MAIN.CPP, MSTEP2.h and MSTEP2.LIB. The file MAIN.CPP provide examples of MSTEP2 command. If you have any question of MSTEP2 command , you could trace the source file MAIN.CPP.

The pannel of MTEST.EXE has three area :

- (1) Limit switch condition area : it indicate the limit switch condition.
- (2) Motion parameter area : it shows every variable of motion parameter.
- (3) Command area : you can select any command in this area and to execute it.

You can press any key to stop X-axis and Y-axis.

There are three command MSTEP2_INTP_LONG_LINE(), MSTEP2_INTP_CIRCLE() and MSTEP2_INTP_ARC() that only can be immediately stopped by /EMG switch.

2 Axes Stepping Mtor Control Card				version 0.9	C. C. M 3/15/9
Limit Switch				MSTEP2_SET_VAR	MSTEP2_HSP_MOVE
ORG1	ORG2	TP11	TPEFF		
LS11	LS21	TP12		MSTEP2_SET_MODE	MSTEP2_CSP_MOVE
LS12	LS22	TP13			
LS13	LS23	TP14	/TPG	MSTEP2_SET_DIRDEF	MSTEP2_SLOW_DOW
LS14	LS24	TP21	TPG1		
FFEF	CPUS	TP22	TPG2	MSTEP2_SET_SERVO_ON	MSTEP2_SLOW_STO
FFFF	XSTP	TP23			
/EMG	YSTP	TP24		MSTEP2_STOP_X	MSTEP2_LSP_PULSE_MOV
Motion Parameter					
DDA cycle	=	5		MSTEP2_STOP_Y	MSTEP2_HSP_PULSE_MOV
ACC/DEC	=	5			
Low Speed	=	10		MSTEP2_STOP_ALL	MSTEP2_INTP_PULS
High Speed	=	120			
X output mode	=	CW/CCW		MSTEP2_RESET_SYSTEM	MSTEP2_INTP_LINE
Y output mode	=	CW/CCW			
X direction	=	NORMAL		MSTEP2_LSP_ORG	MSTEP2_INTP_LONG_LIN
Y direction	=	NORMAL			
X servo on	=	ON		MSTEP2_HSP_ORG	MSTEP2_INTP_CIRCL
Y servo on	=	ON			
				MSTEP2_HSD_ORG	MSTEP2_INTP_ARC
				MSTEP2_LSP_MOVE	----- testing -----
Press any key, /EMG, to stop !!					

5.2 Windows example

The project1.exe (source file included) is a example for ENCODER3 card and STEP200 card. It has windows95 and NT edition.

The pannel of project1.exe has four area :

- (1) Limit switch condition area : it indicate the limit switch condition.
- (2) Motion parameter area : it shows every variable of motion parameter.
The parameters can be modify directly, then choose the corresponding command to send command into STEP200 card.
- (3) Command area : you can select any command in this area and to execute it.
- (4) The lower-right encoder sub-window shows the address(decimal), counter value and index value. When click the Update Parameters button, it will shows a dialog for selecting the counting mode and times mode.

