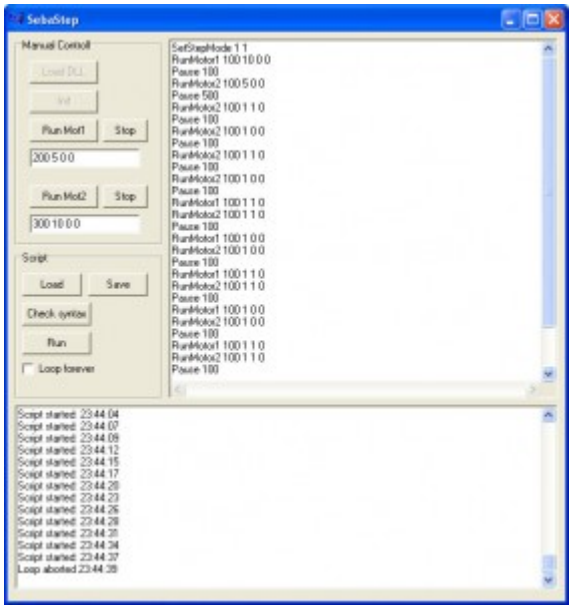
Pavlin.si -> same zanimive stvari

Šola, MTB, potepanja, elektronika, foto

Višinski diagram	Manjka GPX zapis.

Stepper Bee+

Pred časom mi je pod roke prišel mali kontrolerček koračnih motorjev Stepper Bee+. Ker je priloženi software bolj čuden, sem naredil svojega. V bistvu je en enostaven interpreter, ki uporablja modulu priloženo dll knjižnico.



Za arhiv celotnega projekta za borland c++ builder pošlji mail.

Tule je zip arhiv, v katerem je EXE, DLL in help datoteka. (MD5 hash: e0fd54f766a4c0b8b64840ffa62b244d, velikost 412.59KB)

Ukazi so:

Commands

SetStepMode *M1Mode M2Mode*

The StepMode can be set to one of three possible options... Full Step, Wave Step and Power Off. The SetStepMode command has therefore three possible values for its

parameters *M1Mode* and *M2Mode*:

M1Mode, M2Mode	Step mode
0	Wavestep mode
1	Full step mode
2	Power Off mode

These mode settings are independent for motors 1 and 2 and can be changed at any time, even during a step interval.
StopMotor1 *outputs*

StopMotor2 *outputs*
To terminate the current task being performed by motor1 or motor2 immediately while updating the current state of the other switching outputs.

Outputs – integer in the range 0 to 7 corresponding to the bit pattern for on/off of the additional switching outputs associated with motor 1. e.g. a value of 5 (which is 00000101 in binary) would result in outputs 1 and 3 being on.

RunMotor1 *steps interval direction outputs*

RunMotor2 *steps interval direction outputs*

Steps – integer in the range 1 to 16000 corresponding to the number of steps to execute
Interval – integer in the range1 to 16000 corresponding to the time interval in milliseconds between each step

Direction – integer in the range 0 to 1. Zero corresponds to forward and 1 to reverse.

Outputs – integer in the range 0 to 7 corresponding to the bit pattern for on/off of the additional switching outputs associated with motor 1. e.g. a value of 5 (which is 00000101 in binary) would result in outputs 1 and 3 being on.

Example:

To run Motor1 forward for 200 steps with 50ms between steps and all additional switching outputs off would use the following command:

RunMotor1 200 50 0 0

Pause *msec*

Command halts parsing for specified time in milliseconds. Time resolution is 10ms. As consequrnce, the interval *msec* is rounded to nearest 10ms and shortest interval is 10ms.

WaitMotor1

WaitMotor2
Command waits for motor 1 or motor 2 to stop motion.

*comment*

Comments are lines starting with # and one white space.