

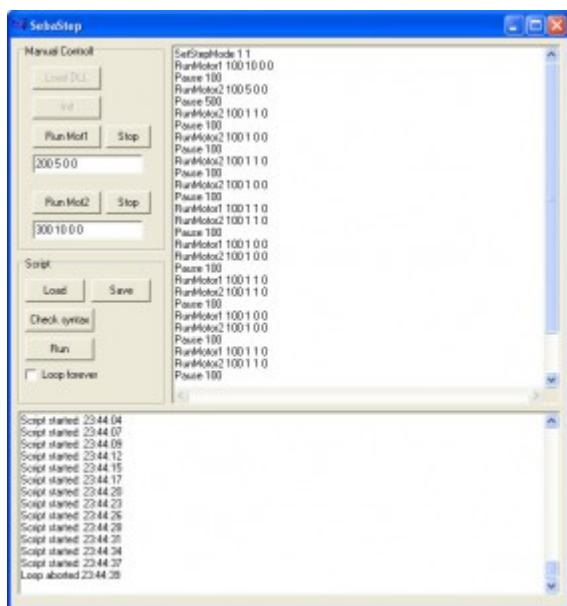
Pavlin.si -> same zanimive stvari

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 range 1 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 consequence, 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.