

MMC-200

Series



Modular Motion Control System Reference Manual

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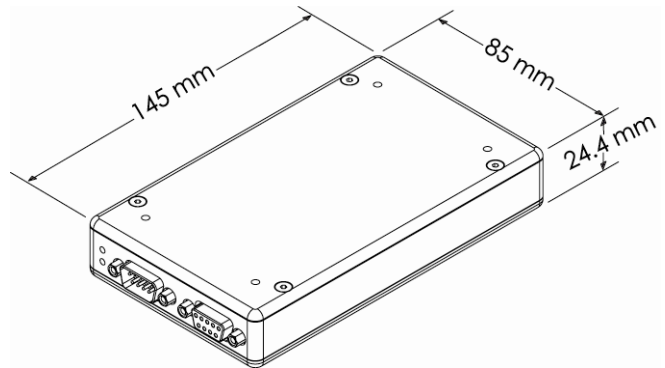
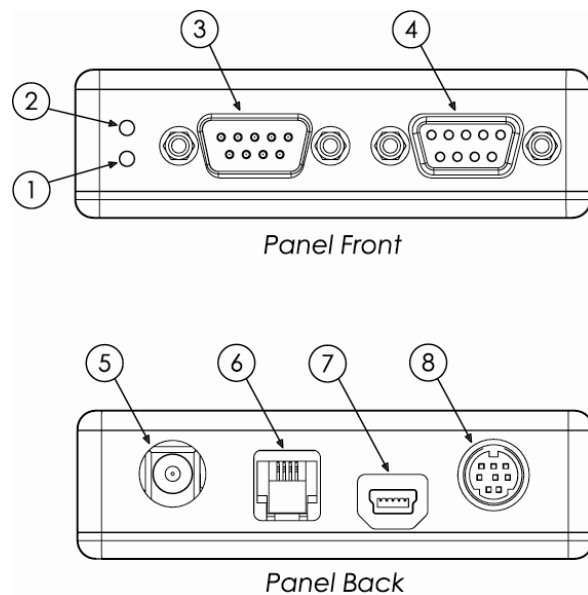
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HCG	Home Configuration	41	UMX	Max Micro Steps	80
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ITG	Integrator Term Gain	43	VEL	Velocity	82
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LIM	Limit Status	50	ZRO	Zero Position	89
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1. Introduction

1.1 Product Description

The MMC-200 is a high-performance integrated stepper motor controller/driver designed to be used as a standalone single axis unit, or stacked as a compact multi-axis module. The MMC-200 is capable of driving a stepper motor with a resolution as fine as 4096 microsteps per fullstep in open loop. The closed loop resolution is dependent on the resolution of the encoder (typically 50 nm).



1. LED Error Indicator 1
 - a. Red – An error has occurred
2. LED Addressing Indicator 2
 - a. Orange – Controller is Unaddressed
 - b. Green – Controller has an address and is ready
3. Encoder Input, Male D-Sub 9 Pin Connector
4. Motor/Axis Output, Female D-Sub 9-Pin Connector
5. Power Supply, +24VDC, Regulated
6. RS485 Intermodular Connector
7. USB Connector
8. I/O Connector

1.2 Features

- Integrated controller/driver for stepper motors
- Compact, modular design allows for bench-top or standard 2U height rack mounting
- Configurable as a standalone unit or stackable up to 16 axes
- Open loop/closed loop operation
- Open loop resolution of 4096 Micro steps per full step*
- Closed loop resolution dependent on the encoder (typically 50 nm)
- A quad B encoder feedback
- USB interface (one interface for up to 99 axes)
- Windows GUI and LabVIEW VI

1.3 Package Contents

If product is damaged or there are missing components, contact MICRONIX USA immediately. Do not discard product packaging in case of return shipment.

Package Contents:

- MMC-200 Controller
- User Manual
- Supplemental CD
- Power Cable

2. Quick Start Guide

2.1 Quick Start Guide Overview

The following Quick Start Guide is intended to provide a basic set-up of the MMC-200 in the least amount of time. The following paragraphs will provide a walkthrough of the steps needed to set-up the controller and verify that the system is working correctly.

1. Install Drivers

- a. To ensure correct communication between the module and PC, install the proper drivers onto the communicating computer prior to connecting the MMC-200.
- b. The drivers may be found on the supplemental installation CD or can be downloaded from: <http://www.ftdichip.com/Drivers/VCP.htm>

2. Connect Motion Devices

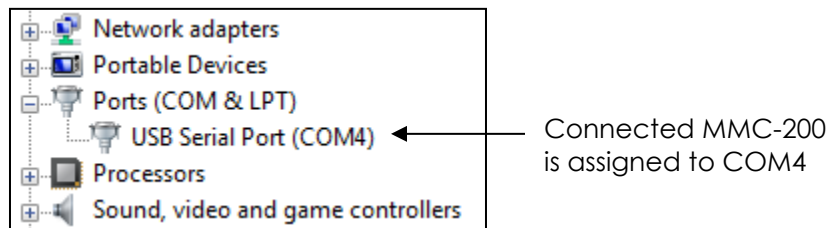
- a. A single MMC-200 controller is capable of driving one stepper motor in either open or closed loop.
- b. Connect the male D-sub 9-pin stepper motor cable to the Motor/Axis Input (as shown in the *Product Description*).
- c. If applicable, connect the female D-sub 9-pin closed loop feedback cable to the Encoder Input.

*This value is theoretical actual value with vary depending on the attached stepper motor.

3. Connect Module/Stack to PC

- a. Use the supplied Mini USB to USB cable to connect the MMC-200 controller to the communicating PC. Only one USB cable is required per module/stack.

4. Power Up Controller
 - a. Connect the controller to a 24V, regulated power supply with the correct amperage rating.
 - b. Each MMC-200 requires 1A. If powering a stack; add up the amperage requirements of the individual controllers to determine the necessary power supply for the stack.
5. Check COM Port
 - a. It is necessary to note the COM Port assigned to the MMC-200 when connecting to a PC.
 - i. In Windows Vista Open the Device Manager:
 - 1 Windows Logo (in the bottom left corner by default)
 - 2 Control Panel
 - 3 Device Manager
 - ii. In Window XP Open Device Manager:
 - 1 Start (in the bottom left corner by default)
 - 2 Control Panel
 - 3 System
 - 4 select the Hardware tab
 - 5 Click the device manager button
 - iii. In Windows 7 Open the Device Manager:
 - b. After powering up the controller (Step 4), note the USB Serial Port assigned. See the figure below showing a snapshot of the Device Manager window:



6. Continue to Quick Start MMC-100 Motion Controller Platform
 - a. The following section will help you get running with the MMC-100 Motion Controller Platform program.

2.2 Quick Start MMC-100 Motion Controller Platform

The following Quick Start Guide is intended to provide a basic set-up of the MMC-100 MCP program. The MMC-200 can be run with the MMC-100 MCP though some commands will not show up in the settings tab; you will be able to access the full functionality of the MMC-200 with the MMC-100 MCP. The following paragraphs will provide a walkthrough of the steps needed to install the program and verify that the system is working correctly.

1. Pre-Installation

- a. This guide assumes you have already run through the previous Quick Start guide and that the controller is on and connected to a Com port on your computer. Please verify that this is true.
- b. You will need the .NET Framework 4.0. If you are unsure if you have the .NET Framework 4.0 follow these steps.
 - i. Open the start menu (windows icon if using Vista).
 - ii. Open the Control Panel
 - iii. Open "Add or Remove Programs" ("Programs and Features" if using Vista)
 - iv. Scroll through the list and find "Microsoft .NET Framework" If it is 4.0 skip to step-2. Otherwise continue with step c.
- c. To install the .NET Framework 4.0 you will need a connection to the internet.
 - i. Navigate to this site:
<http://www.microsoft.com/downloads/details.aspx?FamilyID=9cfb2d51-5ff4-4491-b0e5-b386f32c0992&displaylang=en>
 - ii. Download and run the web installer
 - iii. At the conclusion of this install you will be asked to restart your computer. Do this now.

2. Install

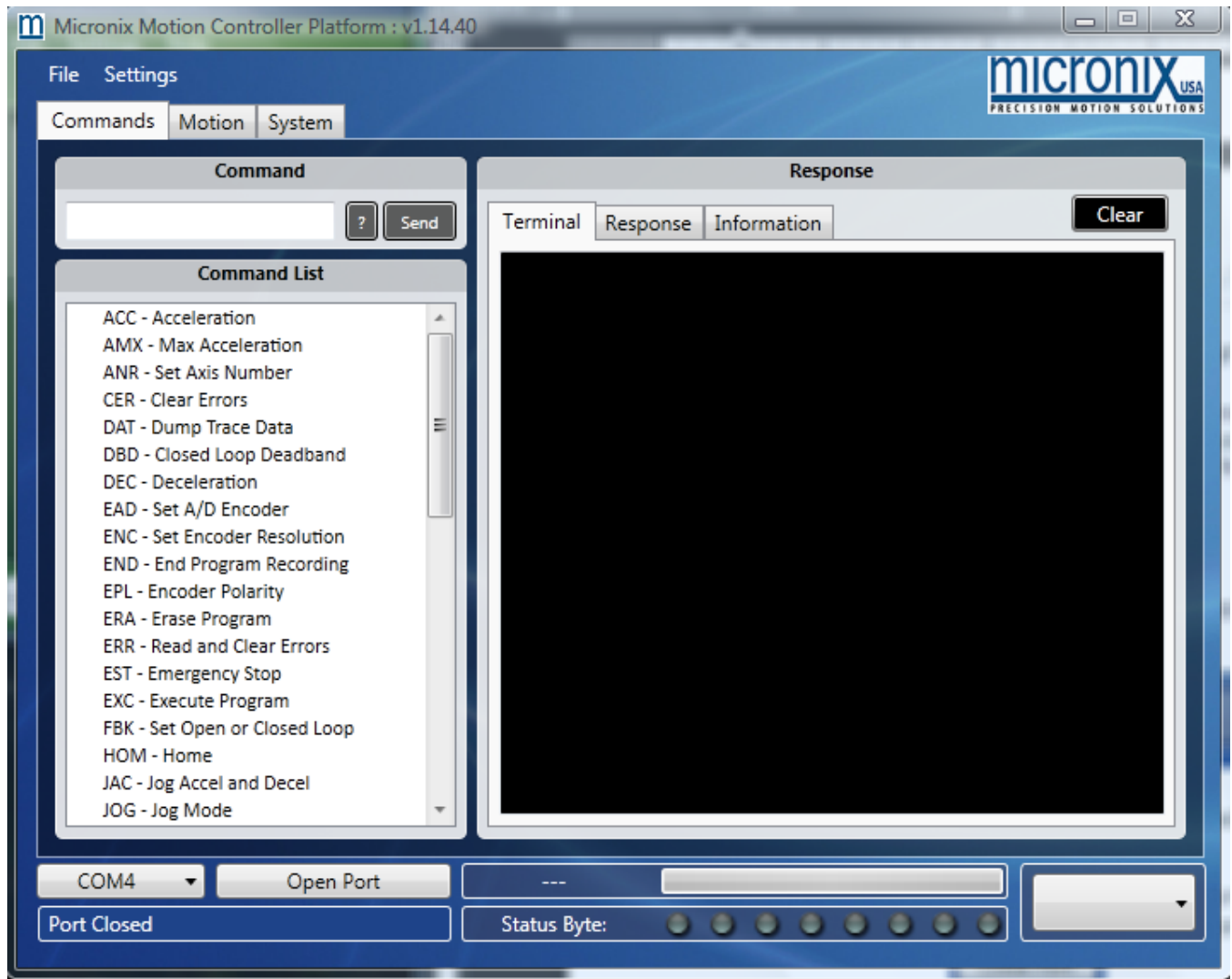
- a. To install the MMC-100 motion controller platform double click the setup.exe file on the supplied CD and follow the on screen instructions.

3. Run

- a. The installer placed a start menu short-cut to the MMC-100 MCP program. Make sure that your MMC-200 is connected to your computer, powered on, and connected to a valid COM port as discussed in section 2.1
- b. Open the start menu (or windows icon for vista)
- c. Open the 'all programs' tab
- d. Open the MICRONIX USA folder
- e. Run the MMC-100 MCP program

2.3 Using the MMC-100 Motion Controller Platform

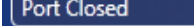
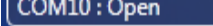
In the Quick Start Guide Overview you connected your MMC-200 to your computer. In the Quick Start MMC-100 Motion Controller Platform you installed and ran the MMC-100 MCP software. This section will describe the capabilities of the MMC-100 MCP program and give you a brief understanding of how to use it.



1. Port Control – The picture below depicts the program when the Port has been opened



- a. Select the COM port associated with your MMC-200 **COM10** as discussed in section 2.1, step 5.
- b. Click the Open Port button to connect to the MMC-200 **Open Port**
 - i. This button should change giving you the option to close the port **Close Port**

- c. The Port field should change to indicate the Port is Open   and the terminal should populate with some information about the system and then turn blank. You are now ready to start moving a stage with your MMC-200. For more information about this program see the MMC-100 MCP program guide.
2. More information – more information about the MMC-100 MCP can be found in the MMC-100 MCP program guide.

3. Technical Information

3.1 MMC-200 Specifications

Parameter	Description
Axes	1 (stackable up to 99 axes)
Motor Type	Stepper motors
Interface	USB 2.0 compliant
Commands	ASCII Commands
Trajectory Mode	Trapezoidal velocity profile
Servo Clock	10 kHz
Trajectory Update	1 kHz
Power Supply	Regulated 24V DC (1A per module/axis*)
Enclosure Dimensions	145 x 85 x 25
Software Interface	MMC-200 MCP, LabVIEW VI's

*A single power supply may be used per stack. Each module/axis requires 1A maximum depending on the type of motor it is driving, therefore add up Individual module amperages to determine the power supply amperage requirement.

3.2 Serial Port Setup

If the MMC-200 is not automatically recognized by your computer, you will have to first install the FTDI interface drivers before communicating with the controller. The drivers are supplied on the supplemental CD under the folder *MMC-200 Drivers* or can be downloaded from:

<http://www.ftdichip.com/Drivers/VCP.htm>

Below are the virtual RS-232 configuration settings necessary for correct communication setup:

Software Parameter	Setting
Data Bits	8
Stop Bits	1
Parity	No
Handshake	No
Baud rate	38400

3.3 RJ11 RS485 Bus

The RS485 Intermodular RJ11 connector connects directly to the same Serial bus as the FTDI interface above. The RS485 line needs a terminating resistor of 22k Ω or higher. This connector can be used to communicate with the MMC-100 in the place of the USB connection. For more on the RS-485 Intermodular RJ11 connector see the Appendix 6.4.

4. Operation

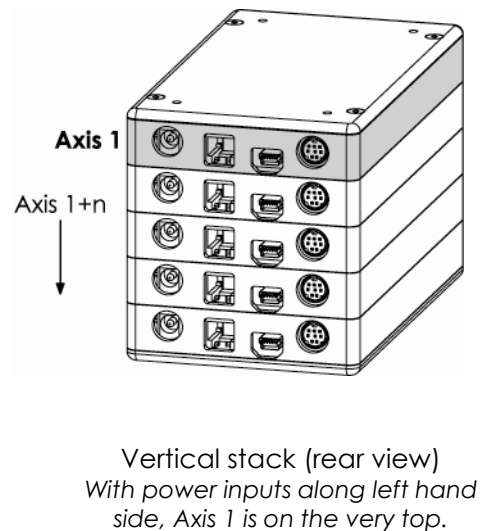
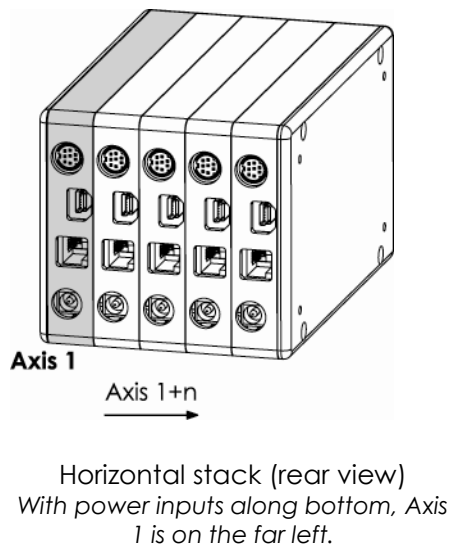
4.1 Axis Addressing

Auto Addressing is the default method of assigning axis numbers on start up. Controllers are automatically assigned axis numbers on every power up, starting with axis 1 and increasing consecutively until reaching axis 99.

Manual axis numbers may be assigned to a unique controller using the ANR Command. This overrides Auto Addressing, as the controller stores the axis number until reassigned or reset back to Auto Addressing. In the case of having a mix of manually assigned and auto addressed controllers, the Auto Addressed axis numbers increase consecutively after each manually assigned axis in the stack. For example; in a stack of 5 controllers with the third controller manually assigned to axis 10, the axis numbers will read: 1, 2, 10, 11, 12

If two controllers are accidentally assigned the same axis number, use a global command to reset all controllers back to Auto Addressing.

The figures shown below illustrate axis numbers for a 5 module stack with Auto Addressing assigned. Axis 1 is noted and shown in grey.



4.2 Feedback Control

The MMC-200 has four different movement modes of operation. When executing a move command, the controller will drive a stage differently when set to different modes. The FBK command is used to switch between these modes.

The first mode (nFBK0) is a traditional Open Loop. It follows a standard trapezoidal velocity characteristic. It bases the transition between acceleration, constant velocity and deceleration on counting steps of the stepper motor. This requires the FSR, LSP, and GRR settings to be correctly set for the attached motor. This feature is only available in firmware version 1.3.1 and higher.

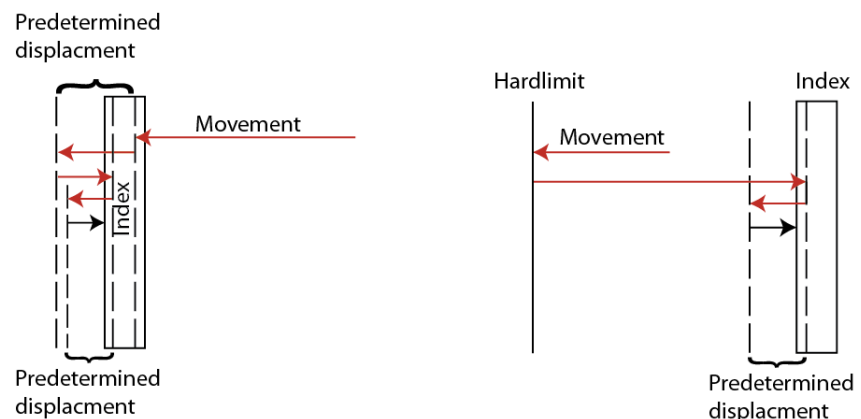
The second mode (nFBK1) is a version of closed loop; meaning it takes position data from an attached encoder and uses it to ensure that it stops at the desired position. In this mode, the controller operates in open loop, but makes small open loop corrections to adjust the end position to within the deadband (DBD).

The third mode (nFBK2) is a version of closed loop; meaning it takes position data from an attached encoder and uses it to ensure that it stops at the desired position. In this mode the controller runs in the first open loop mode (nFBK0) until it reaches the deceleration point. At this point it activates the PID and actively corrects its trajectory to arrive at the correct position. This, unlike the first two modes can guarantee position within the specified deadband (DBD Command). However, this mode cannot guarantee a desired trajectory.

The fourth mode (nFBK3) is not applicable on the MMC-200.

4.3 HOM, MLN, and MLP

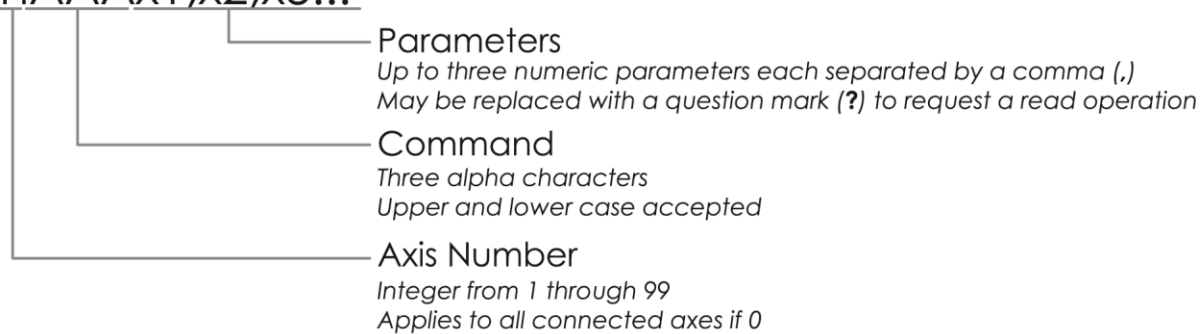
The HOM command all requires the attached stage to have an encoder. The MLN and MLP commands require either an attached encoder, or limit switches. HCG, LCG, LDR and LPL are all commands that affect the operation of either HOM or MLN and MLP. The HOM command will move negative direction by default. This can be changed using the HCG command. If the stage is above the index, it will move until it reaches the index then move a predetermined distance out of the index in the negative direction. The stage will then travel in the positive direction at a slower speed stopping at the edge of the index. If the stage is below the index it will move until it reaches a hard limit or the maximum travel. It then reverses direction and proceeds until it reaches the index. It will then travel a predetermined distance out of the index in the negative direction and finally travel toward the index at a slower velocity finally resting on the edge of the index. The HOM command will always home to the negative side of the limit.



5. Commands

5.1 Command Line Syntax

nAAAx1,x2,x3...



There are three components to every command prompt. The first is the "Axis Number" which designates which controller, or axis, will receive the command. If the "Axis Number" is 0, then the command will be sent globally to all connected controllers. It is possible to connect up to 99 controllers; therefore the "Axis Number" will be an integer value from 0 through 99.

The second component is the "Command", which is always comprised of three letters. Each command is outlined, along with its corresponding parameters, in the *Command Description* section 5.9 of this manual.

The third and final component is the "Parameter". This portion is command dependent, meaning that the parameter value will change depending on the specific requirements of the "Command". Where applicable, a question mark (?) may be substituted to initiate a read operation which will return information regarding the particular command. There may be up to three separate parameters for a particular command, each parameter value is separated by a comma (,).

All white space (blank spaces) are ignored in the command format. The following are examples of equivalent commands:

```
4TRM13,45
4 TRM 13 , 45
```

5.2 Command Line Format

Commands are first executed in the order that they are input, then line by line. This means that two commands on the same line are executed significantly closer to each other than if they were on two separate lines. Each command is separated by a semicolon (;) and every command line ends in a terminator (EX: carriage return). The following is an example of a command line entry:

```
1MVR16;3MVR12      | Axis 1, Move 16 mm [16 degrees]; Axis 3, Move 12 mm [12 degrees]
```

Using multiple commands on the same command line allows for synchronization of different commands to different axes. Up to 8 commands are allowed per command line.

Only one read operation is allowed per line. The controller will not send information unless requested to do so by a read operation.

5.3 Global Commands

Some commands have the option of being called globally. This means that you can send the same command to all available axes. To do this, replace the axis number of a global command with a '0'. For example; 0ACC 50 will set the acceleration of all available axes to 50 mm/s² [degrees/s²].

5.4 Multiple Parameters

When dealing with a command that has multiple parameters, it is possible to change a single parameter by omitting numbers for the parameters that will remain unchanged. For example; 4PID, , 3 will only change the third parameter to a new value, "3".

5.5 Synchronous Move

It is possible to move multiple motion devices at the same time, or extremely close to, by setting up and executing a synchronous move. To set up a synchronous move, use the MSA and MSR commands on the same command line (up to 8 allowed) or on separate lines followed by a line terminator. To execute the move, use the RUN command on the proceeding command line followed by a line terminator. For example;

1MSA4 ; 2MSA4 ; 3MSA4	Axis 1, Move 4mm; Axis 2, Move 4mm; Axis 3 Move 4mm
0RUN	Run Synchronous Move
Or	
1MSA4	Axis 1, Move 4mm
2MSA4	Axis 2, Move 4mm
3MSA4	Axis 3 Move 4mm
0RUN	Run Synchronous Move

5.6 Internal Programming

A program may be used to save time when repeatedly using a sequence of commands. Each controller or axis must be programmed individually; however, multiple controllers may execute the same program at the same time. A list of available program numbers may be viewed with the PGM? command. Existing program numbers cannot be overridden unless previously erased using the ERA command.

To record a program sequence, enter the PGM command on a unique line followed by a line terminator. End a program sequence by entering the END command on a unique line followed by a line terminator. When you want to execute this program, use the EXC command. See the *Summary of Commands* page for a list of program compatible commands and more information about the PGM, END and EXC commands.

5.7 Terminating Characters

When communicating with the controller, it is necessary to note the terminating characters involved in transmitting and receiving data. To send data to the controller, enter the desired commands in the command line followed by the new line and carriage return terminating characters [\n\r], or just the carriage return terminating character [\r]. When receiving, each line of data will be followed by the new line terminating character [\n] and the final line will end in the new line and carriage return terminating characters [\n\r]. The Hexadecimal value for new line [\n] is 0X0A and for carriage return [\r] is 0X0D. The following is an example of data transmission:

1VEL0.005 \n\r	Axis 1, Set velocity to .005 mm/s [degrees/s ²] [New line, Carriage Return]
----------------	---

Summary of Commands

Command	Description	During Motion		Real-time		Program		Global		Page
		Set	Read	Set	Read	Set	Read	Set	Read	
ACC	Acceleration		✓	✓	✓	✓		✓		16
AMX	Maximum Allowable Acceleration		✓		✓			✓		17
ANR	Set Axis Number		✓	✓	✓			✓*		18
CER	Clear Errors	✓		✓				✓		19
CFG	Configuration Mode		✓	✓	✓					20
CST	Correction Sample Time		✓	✓	✓			✓		21
CVL	Correction Velocity		✓	✓	✓			✓		22
DAT	Dump Trace Data		✓		✓					23
DBD	Closed Loop Deadband		✓	✓	✓			✓		24
DEC	Deceleration		✓	✓	✓	✓		✓		25
DEF	Restore Factory Defaults			✓				✓		26
DST	Derivative Sample Time		✓	✓	✓			✓		27
DTG	Derivative Term Gain		✓	✓	✓			✓		28
ENC	Select Encoder Resolution		✓	✓	✓			✓		29
END	End Program Recording					✓				30
EPL	Encoder Polarity		✓	✓	✓			✓		31
ERA	Erase Program			✓						32
ERG	Error Gain		✓	✓	✓			✓		33
ERR	Read and Clear Errors		✓		✓					34
EST	Emergency Stop	✓						✓		35
EXC	Execute Program			✓				✓		36
FBK	Set Open or Closed Loop Mode		✓	✓	✓					37
FMR	Upload Firmware			✓						38
FSR	Full Steps Per Rev		✓	✓	✓			✓		39
GRR	Gear Ratio		✓	✓	✓			✓		40
HCG	Home Configuration			✓	✓			✓		41
HOM	Home		✓	✓	✓	✓		✓		42
ITG	Integrator Term Gain		✓	✓	✓			✓		43
IST	Integrator Sample Time		✓	✓	✓			✓		44
IWL	Integrator Windup Limit		✓	✓	✓			✓		45
JAC	Jog Acceleration and Deceleration		✓	✓	✓			✓		46
JOG	Jog Mode	✓		✓				✓		47
LCG	Limit Configuration		✓	✓	✓			✓		48
LDR	Positive/ Negative Limit Location		✓	✓	✓			✓		49
LIM	Limit Status		✓		✓					50
LSP	Lead Screw Pitch		✓	✓	✓			✓		51
LST	Program List		✓		✓					52
LPL	Limit Switch Polarity		✓	✓	✓			✓		53

Continued...

Command	Description	During Motion		Real-time		Program		Global		Page
		Set	Read	Set	Read	Set	Read	Set	Read	
MCM	Max Motor Current		✓		✓					54
MCS	Motor Current Setting		✓	✓	✓			✓		55
MLN	Move to Negative Limit			✓		✓		✓		56
MLP	Move to Positive Limit			✓		✓		✓		57
MOT	Toggle Motor On/Off		✓	✓	✓			✓		58
MPL	Motor Polarity		✓	✓	✓			✓		59
MSA	Synchronous Move – Absolute			✓				✓		60
MSR	Synchronous Move – Relative			✓				✓		61
MVA	Move Absolute			✓		✓		✓		62
MVR	Move Relative			✓		✓		✓		63
PGL	Loop Program		✓	✓	✓			✓		64
PGM	Begin Program Recording			✓		✓				65
PGS	Run Program At Start-Up			✓	✓			✓		66
PID	Set Feedback Constants		✓	✓	✓					67
POS	Read Current Position		✓		✓					68
REZ	Set Resolution		✓	✓	✓					69
RST	Perform Soft Reset			✓				✓		70
RUN	Start Synchronous move			✓				✓		71
SAV	Save Axis Settings			✓				✓		72
STA	Status Byte		✓		✓					73
STP	Stop Motion	✓		✓				✓		74
SVP	Save Startup Position		✓	✓	✓	✓		✓		75
SYN	Sync					✓		✓		76
TLN	Negative Soft Limit Position		✓	✓	✓	✓		✓		77
TLP	Positive Soft Limit Position		✓	✓	✓	✓		✓		78
TRA	Perform Trace		✓	✓	✓	✓		✓		79
UMX	Max Micro Steps		✓		✓					80
UST	Micro Steps		✓	✓	✓			✓		81
VEL	Velocity	✓	✓	✓	✓	✓		✓		82
VER	Firmware Version		✓		✓					83
VMX	Max. Allowable Velocity		✓		✓					84
VRT	Encoder Velocity		✓		✓					85
WST	Wait For Stop					✓				86
WSY	Wait For Syc					✓		✓		87
WTM	Wait For Time Period					✓				88
ZRO	Zero Position			✓		✓		✓		89
ZZZ	Take Axis Offline			✓				✓		90

* see ANR command page 18 for more info

5.8 Command Descriptions



Acceleration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the desired acceleration for the specified axis, distinct from the deceleration [DEC]. The acceleration value must be less than the maximum acceleration [AMX] for the command to be accepted.					
Returns:		A read operation returns the acceleration value in mm/s ² for the specified axis.					
Syntax:		nACCx – Standard syntax nACC? – Read acceleration value 0ACCx – All axes set acceleration value Error [#]: ACC? – Read operation with missing axis number [27] nACC – Missing acceleration parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Acceleration ? – Read acceleration value					
Parameter Range:		n – 0 to 99 x – 000.001 to AMX (500.000 mm/s ² [degrees/s ²])					
Related Commands:		DEC, VEL, JAC, AMX					
Example:		3ACC0.250 Axis 3, Set acceleration to 0.25mm/s ² [degrees/s ²] – 4ACC? Axis 4, Read acceleration value					



Maximum Allowable Acceleration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓			✓	
Command Description:		This command is used to set the maximum allowable acceleration for the specified axis.					
Returns:		A read operation returns the maximum allowable acceleration value in mm/s ² for the specified axis.					
Syntax:		nAMXx – Standard syntax nAMX? – Read maximum allowable acceleration value 0AMXx – All axes set maximum allowable acceleration value Error [#]: AMX? – Read operation with missing axis number [27] nAMX – Missing maximum acceleration parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Maximum acceleration ? – Read maximum allowable acceleration value					
Parameter Range:		n – 0 to 99 x – 000.001 to 500.000 mm/s ² [degrees/s ²]					
Related Commands:		DEC, VEL, JAC, VMX, ACC					
Example:		2AMX1.500 Axis 2, Set max acceleration to 1.500 mm/s ² [degrees/s ²] – 6AMX? Axis 6, Read max acceleration value					



Set Axis Number

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓*	
Command Description:		<p>This command is used to override Auto Addressing by manually assigning an axis number to a controller. Auto Addressing is the default method of assigning axis numbers on power up and may be reassigned to an axis by substituting a "0" for the parameter value. Simultaneous axis swapping is possible by using multiple ANR commands on the same command line.</p> <p>*This command can be called globally by specifying a '0' for the axis number; however it will only work if the new axis number parameter is set to '0' for auto-addressing.</p>					
Returns:		<p>A read operation returns the following axis number values for the specified axis:</p> <p>0 – Auto Addressing assigned (default)</p> <p>1-99 – Manually assigned, axis number displayed</p>					
Syntax:		<p>nANRx – Standard syntax</p> <p>nANR? – Read axis number value</p> <p>Error [#]:</p> <p>ANR? – Read operation with missing axis number [27]</p> <p>nANR – Missing new axis number parameter [28]</p> <p>ANRx – Missing axis number [30]</p>					
Parameter Description:		<p>n[int] – Axis number</p> <p>x[int] – New axis number, 0 for Auto Addressing</p> <p>? – Read axis number value</p>					
Parameter Range:		<p>n – 0 to 99</p> <p>x – 0 to 99</p>					
Related Commands:		None					
Example:		<p>5ANR1 ; 1ANR5 Simultaneous axis swapping: Axis 5, Set to axis 1 ; Axis 1, Set to axis 5</p> <p>–</p> <p>4ANR0 Axis 4 , Set to Auto Addressing. However it will remain axis 4 until the MMC-200 is reset</p>					

CER

Clear Errors

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
✓		✓				✓	
Command Description:		This command is used to clear all error messages without reading them.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nCER – Standard syntax 0CER – All axes clear error messages					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		ERR					
Example:		1CER Axis 1, clear error messages – 0CER All axes, clear error messages					



Configuration Mode

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This setting determines whether the system resolution is calculated from the LSP, GRR, FSR settings (CFG == 0), or if it is entered directly by the user (CFG==1).					
Returns:		0 – Resolution is automatically calculated 1 – Resolution is set manually by the user					
Syntax:		nCFGx – Standard syntax nCFG? – Read configuration setting 0CFGx – Set all axes to configuration x Error [#]: CFG? – Read operation with missing axis number [27] nCFG – Missing Configuration parameter [28]					
Parameter Description:		n[int] – Axis number x[int] – Configuration Mode ? – Read Configuration Mode					
Parameter Range:		n – 0 to 99 x – 0 or 1					
Related Commands:		LSP, GRR, FSR					
Example:		1CFG0 Axis 1, resolution automatic configuration – 5CFG1 Axis 5, resolution manual configuration					

Correction Sample Time

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the correction sample time. Sample rate = 5kHz/CST. This term is only used the FBK modes 1. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The time value for the correction sample period					
Syntax:		nCSTx – Standard syntax Error [#]: CSTx – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[float] – Sample time ? – Read correction sample time					
Parameter Range:		n – 1 to 99 x – 1 to 5000					
Related Commands:		CVL, FBK					
Example:		2CST1 Axis 2, Set correction sample time to 1]					

Correction Velocity

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the correction velocity. This term is only used the FBK modes 1. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The value for the correction velocity					
Syntax:		nCVL – Standard syntax Error [#]: CVLx – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[float] – Correction velocity ? – Read correction velocity					
Parameter Range:		n – 1 to 99 x – 000.001 to VMX [default: 50 µm /s]					
Related Commands:		CST, FBK					
Example:		2CVL1 Axis 2, Set correction velocity to 1]					



Dump Trace Data

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command is used to read trace data from a specified axis initially recorded by the trace command [TRA]. The retrieved trace data set is dumped from the controller, consequently allowing the data to be retrieved only once.					
Returns:		A read operation returns the trace data values for the specified axis in the following format: [Theoretical Position (.5nm)], [Actual Position (.5nm)], [DAC Sin], [DAC Cos]					
Syntax:		nDAT? – Read trace data values Error [#]: DAT? – Read operation with missing axis number [27] nDAT – Missing read operation parameter [28]					
Parameter Description:		n[int] – Axis number ? – Read trace data values					
Parameter Range:		n – 1 to 99					
Related Commands:		TRA					
Example:		11DAT?		Axis 11, Read trace data values			



Closed Loop Deadband

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the acceptable deadband and deadband timeout values.					
		Deadband refers to the number of encoder counts (\pm) from the target that is considered acceptable. If the parameter (x1) is set to "0", the controller will continuously oscillate around the target.					
		Deadband timeout refers to the amount of time that the controller will try to move into the deadband area. If the parameter (x2) is set to "0", the controller will seek continuously.					
Returns:		A read operation returns the deadband and deadband timeout values for the specified axis.					
Syntax:		nDBDx1,x2 – Standard syntax nDBD? – Read deadband and deadband timeout values 0DBDx1,x2 – All axes set deadband and deadband timeout values					
		Error [#]: DBD? – Read operation with missing axis number [27] nDBD – Missing deadband and deadband timeout parameter values [28]					
Parameter Description:		n[int] – Axis number x1[int] – Deadband x2[float] – Deadband timeout ? – Read deadband and deadband timeout values					
Parameter Range:		n – 0 to 99 x1 – 1 to 999 encoder counts, x2 – 0 for infinite, Seconds (default 0)					
Related Commands:		ENC, EPL					
Example:		1DBD10,1		Axis 1, Set deadband to 10 encoder counts & deadband timeout to 1 second			
		- 4DBD5,0		Axis 4, Set deadband to 5 encoder counts & deadband timeout to infinite			



Deceleration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the desired deceleration for the specified axis, distinct from the acceleration [ACC]. The deceleration value must be less than the maximum acceleration value [AMX] for the command to be accepted.					
Returns:		A read operation returns the deceleration value in mm/s ² for the specified axis.					
Syntax:		nDECx – Standard syntax nDEC? – Read deceleration value 0DECn – All axes set deceleration value Error [#]: DEC? – Read operation with missing axis number [27] nDEC – Missing deceleration parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Deceleration ? – Read deceleration value					
Parameter Range:		n – 0 to 99 x – 000.001 to AMX (500.000 mm/s ²) [degrees/s ²]					
Related Commands:		ACC, AMX, VEL					
Example:		2DEC1.25 Axis 2, Set deceleration to 1.25 mm/s ² [degrees/s ²] - 7DEC? Axis 7, Read deceleration value					

DEF

Restore Factory Defaults

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command restores the factory default parameters.					
Returns:		A read operation is not available with this command.					
Syntax:		nDEF – Standard syntax Error [#]: DEF – Missing axis number [30]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		SAV					
Example:		1DEF Axis 2, Set default parameters]					



Derivative Sample Time

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the Derivative sample time. Sample rate = 5kHz /IST. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The time value for the Derivative sample period					
Syntax:		nDST – Standard syntax Error [#]: DST – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – Derivative sample time ? – Read derivative sample time					
Parameter Range:		n – 1 to 99 x – 1 to 5000					
Related Commands:		PID, FBK					
Example:		2DST1 Axis 2, Set Derivative sample time to 1]					



Derivative Term Gain

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change derivative Term gain. Dterm*DTG, Strengthens the effect of the dTerm. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The time value for the correction sample period					
Syntax:		nDTGx – Standard syntax Error [#]: DTGx – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – derivative gain ? – Read derivative gain value					
Parameter Range:		n – 1 to 99 x – 1 to 5000					
Related Commands:		PID, FBK, DST					
Example:		2DTG1 Axis 2, Set Derivative gain term to 1]					



Set Encoder Resolution

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the desired encoder resolution for the specified axis. When a digital encoder is connected, encoder resolution is determined by the encoder itself. Analog encoder resolution can be set by the controller.					
Returns:		A read operation returns the encoder resolution value for the specified axis.					
Syntax:		nENCx – Standard syntax nENC? – Read encoder resolution value 0ENCx – All axes execute encoder resolution value Error [#]: ENC? – Read operation with missing axis number [27] nENC – Missing encoder resolution parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Encoder resolution ? – Read encoder resolution value					
Parameter Range:		n – 0 to 99 x – 0.001 to 999.999 $\mu\text{m}/\text{count}$ (milli-degrees/count)					
Related Commands:		EAD					
Example:		2ENC10 Axis 2, Set encoder resolution to 10 microns/count (10 milli- degrees/count)					

END

End Program Recording

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
				✓			
Command Description:		This command is used to exit out of program recording mode, which is initiated by the PGM command. The END command must be placed separately on the last line of the program sequence. The resulting program is saved upon exit for later use.					
Returns:		A read operation is not available with this command.					
Syntax:		nEND – Standard syntax Error [#]: END – Missing axis number [30]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		REC, EXC, PGM					
Example:		<div> <div>1PGM</div> <div>1VEL1;1ACC.5</div> <div>1END</div> </div> <div> <div> Axis 1, Begin program recording</div> <div> Axis 1, Set velocity value to 1 mm/s; Axis 1, Set acceleration value to 0.5 mm/s² [degrees/s²]</div> <div> Axis 1, End program recording</div> </div>					

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to switch the encoder signal polarity for the specified axis. If the controller doesn't seem to be recording encoder position correctly, the polarity of the encoder signals could be reversed. Use this command to switch from the default setting (normal operation, n=0).					
Returns:		A read operation returns the following encoder polarity values for the specified axis: 0 – Normal operation 1 – Reverse operation					
Syntax:		nEPLx – Standard syntax nEPL? – Read encoder polarity value 0EPLx – All axes execute encoder polarity value Error [#]: EPL? – Read operation with missing axis number [27] nEPL – Missing encoder polarity parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Encoder polarity ? – Read encoder polarity value					
Parameter Range:		n – 0 to 99 x – 0 for normal operation, 1 for reverse operation					
Related Commands:		MPL					
Example:		13EPL0		Axis 13, Set encoder polarity to normal operation			
		–					
		6EPL1		Axis 6, Set encoder polarity to reverse operation			

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓					
Command Description:		<p>This command is used to erase a specified program from an axis. Before recording a program, use the LST command to see what program numbers are available for that axis. There are 16 program numbers available allowing up to 16 programs to be stored. An existing program cannot be overwritten and must be erased first. Therefore, use this command to erase the specified program and make space for a new one.</p>					
Returns:		A read operation is not available with this command.					
Syntax:		<p>nERAx – Standard syntax</p> <p>Error [#]:</p> <p>ERAx – Missing axis number [30]</p> <p>nERA – Missing program number parameter [28]</p>					
Parameter Description:		<p>n[int] – Axis number</p> <p>x[int] – Program number to be erased</p>					
Parameter Range:		<p>n – 1 to 99</p> <p>x – 1 to 16</p>					
Related Commands:		LST					
Example:		5ERA4		Axis 5, Erase program 4			



Error Gain

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the error gain. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The gain value for the PID error					
Syntax:		nCST x – Standard syntax Error [#]: ERGx – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – Error Gain ? – Read error gain value					
Parameter Range:		n – 1 to 99 x – 1 to 50000					
Related Commands:		PID, FBK					
Example:		2ERG1 Axis 2, Set Error Gain to 1]					

ERR

Read and Clear Errors

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command is used to read and clear any pending error messages. See the error table on page 5-91 to 5-94					
Returns:		A read operation returns a list of error messages for the specified axis in the following format. "AAA" signifies the specific command name that the error corresponds to. Error Number – Description [AAA]					
Syntax:		nERR? – Standard syntax Error [#]: ERR? – Read operation with missing axis number [123]					
Parameter Description:		n[int] – Axis number ? – Read error messages					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		3ERR? Axis 3, Read error messages					

EST

Emergency Stop

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
✓		✓				✓	
Command Description:		This command is used to stop a specific axis or all connected axes simultaneously in case of an emergency. The controller executes the largest possible deceleration.					
Returns:		A read operation is not available with this command.					
Syntax:		nEST – Standard syntax 0EST – All axes execute emergency stop					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		STP					
Example:		8EST Axis 8, Emergency stop – 0EST All axes, Emergency stop					

EXC

Execute Program

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command is used to execute a specified program for one or multiple axes. If executing a program globally, all connected axes should have individual programs stored under the specified program number prior to execution.					
Returns:		A read operation is not available with this command.					
Syntax:		nEXCx – Standard syntax 0EXCx – All axes execute program Error [#]: nEXC – Missing program number parameter [123]					
Parameter Description:		n[int] – Axis number x[float] – Program number to be executed					
Parameter Range:		n – 0 to 99 x – 1 to 64					
Related Commands:		PGM					
Example:		4EXC5 Axis 4, Execute program 5 – 0EXC2 All axes, Execute program 2					

FBK

Set Open or Closed Loop Mode

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓				
Command Description:		This command is used to select the feedback mode of the controller. See section 4.2 for more details					
Returns:		A read operation returns the following loop mode values for the specified axis: 0 – Open Loop [default] 1 – Open Loop with open loop position correction 2 – Open Loop Movement, Closed Loop deceleration 3 – Not for use on the MMC-200					
Syntax:		nFBKx – Standard syntax nFBK? – Read encoder mode value Error [#]: FBKx – Missing axis number [30] FBK? – Read operation with missing axis number [27] nFBK – Missing closed/open loop parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Open/closed loop mode ? – Read encoder mode value					
Parameter Range:		n – 1 to 99 x – 0 for open loop mode, 1 for open loop with open loop corrections, 2 for open loop with closed loop deceleration, 3 closed loop					
Related Commands:		ENC, EAD, EPL, DBD, PID, CST, CVL, DST, DTG, ERG, IST, IWL, ITG					
Example:		2FBK3		Axis 2, Set closed loop mode			

FMR

Upload Firmware

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓					
Command Description:		This command is used by the bootloader to upload new firmware to the specified axis.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nFMR – Standard syntax Error [#]: FMR – Missing axis number [30]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		VER					
Example:		1 FMR Axis 1, upload new firmware					

Full Steps Per Revolution

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the number of full steps per single revolution of the motor shaft. It is determined by the motor.					
Returns:		A read operation returns the Full Steps Per Revolution for the specified axis.					
Syntax:		nFSRx – Standard syntax nFSR? – Read Full Steps Per Revolution 0FSRx – All axes set Full Steps Per Revolution to x Error [#]: FSR? – Read operation with missing axis number [27] nFSR – Missing full step per rev parameter [28]					
Parameter Description:		n[int] – Axis number x[int] – full steps per revolution ? – Read full steps per revolution value					
Parameter Range:		n – 0 to 99 x – 0 to 10000					
Related Commands:							
Example:		1FSR2000 Axis 1, Set 2000 Full Steps Per Rev – 5FSR? Axis 5, Read Full steps/ Revolution					



Gear Ratio

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the gear ratio. If no gearing is used it should be set to 1:1, which is the default.					
Returns:		A read operation returns the velocity value in mm/s for the specified axis.					
Syntax:		nGRRx,y – Standard syntax nGRR? – Read Gear ratio value OGRRx,y – all axes set gear ratio to x:y Error [#]: GRR? – Read operation with missing axis number [27] nGRR – Missing Gear Ratio parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Leadscrew Revs y[float] – Motor Shaft Revs ? – Read Gear Ratio value					
Parameter Range:		n – 0 to 99 x – 1 – 50000 y – 1 – 50000					
Related Commands:							
Example:		1GRR100,1 Axis 1, 100:1 – 5GRR? Axis 5, Read Gear Ratio value					



Home Configuration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to select the direction of motion when the Home [HOM] command is initialized.					
Returns:		A read operation returns the current direction setting: 0 – Home starts in the direction of the negative limit 1 – Home starts in the direction of the positive limit					
Syntax:		nHCGx – Standard syntax 0HCGx – All axes set direction nHCG? – Read direction setting Error [#]: HCG? – Read operation with missing axis number [27] nHCG – Missing direction setting [28]					
Parameter Description:		n[int] – Axis number x[int] – Set direction of motion.					
Parameter Range:		n – 0 to 99 x – 0 for setting motion in the direction of the negative limit 1 for setting motion in the direction of the positive limit					
Related Commands:		HOM					
Example:		3HCG0		Axis 3, Set initial direction of Home command towards the negative limit			
		–					
		0HCG1		All Axes, Set initial direction of Home command towards the positive limit			



Home

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to find the home (zero) position for a specified axis. An error will occur if there is no encoder signal at the time of execution. Home is configured using the HCG command. This command will jog the stage till it reaches the limit configured by the HCG command. It will then acquire the zero position by looking for the index. This command blocks all communication over the serial port during motion. The controller will buffer all commands sent during this period and execute them once the command has found the index. Caution: if you write too many commands while this command is executing you run the risk of overloading the receive buffer.					
Returns:		A read parameter returns the following calibration values for the specified axis: 0 – Not calibrated to home position 1 – Calibrated to home position					
Syntax:		nHOM – Standard syntax nHOM? – Returns 1 if homed since last startup otherwise returns 0 0HOM – All axes execute home position Error [#]: HOM? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		HCG					
Example:		1HOM Axis 1, Move to home position					

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the sample time for the I Term. Sample rate = 5kHz/IST. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The time value for the correction sample period					
Syntax:		nISTx – Standard syntax Error [#]: IST – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – sample time ? – Read Integrator sample time					
Parameter Range:		n – 1 to 99 x – 1 to 5000					
Related Commands:		FBK, PID, IWL, ITG					
Example:		2IST1 Axis 2, Set integrator sample time to 1]					



Integrator Term Gain

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to change the Integrator gain. iTerm = iTerm/ ITG Lessens the effect of the iTerm. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The Integrator gain value.					
Syntax:		nITGx – Standard syntax Error [#]: ITG – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – Integrator Gain ? – Read integrator gain value					
Parameter Range:		n – 1 to 99 x – 1 to 5000					
Related Commands:		IST, IWL, PID, FBK					
Example:		2ITG1 Axis 2, Set integrator term gain to 1]					

IWL

Integrator Windup Limit

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓	✓			✓	
Command Description:		This command is used to change the upper limit to the integrator wind up. This term is only used the FBK modes 2 and 3. This feature only available in firmware version 1.3.1 and higher.					
Returns:		The integrator windup limit					
Syntax:		nIWLx – Standard syntax Error [#]: IWL – Missing axis number [30]					
Parameter Description:		n[int] – Axis number x[int] – Windup Limit ? – Read Windup Limit value					
Parameter Range:		n – 1 to 99 x – 1 to 999999					
Related Commands:		IST, IWL, ITG, FBK					
Example:		2IWL1 Axis 2, Set integrator windup limit to 1]					



Jog Acceleration and Deceleration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the desired value for the jog acceleration and deceleration for a specified axis. The controller will not allow for JAC values that are greater than AMX.					
Returns:		A read operation returns the jog acceleration and deceleration value in mm/s ² for the specified axis.					
Syntax:		nJACx – Standard syntax 0JACx – All axes execute acceleration value nJAC? – Read acceleration value Error [#]: JAC? – Read operation with missing axis number [27] nJAC – Missing acceleration parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Jog Acceleration ? – Read Jog acceleration value					
Parameter Range:		n – 0 to 99 x – .001 to 500.000 mm/s ² [degrees/s ²]					
Related Commands:		ACC, DEC, AMX					
Example:		4JAC0.1		Axis 4, Set jog acceleration & deceleration to 0.1 mm/s ² [degrees/s ²]			



Jog Mode

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
✓		✓				✓	
Command Description:		This command is used to jog a specific axis, or move continuously in a direction with no target position. The jog velocity is a percentage of the maximum velocity and may be changed on-the-fly by sending another JOG command during motion.					
Returns:		A read operation is not available with this command.					
Syntax:		nJOGx – Standard syntax Error [#]: JOGx – Missing axis number [30] nJOG – Missing velocity parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Velocity					
Parameter Range:		n – 1 to 99 x – -100.000% to 100.000 % (of maximum velocity) – 0 to stop					
Related Commands:		JAC					
Example:		4JOG10 Axis 4, Jog at 10% maximum velocity					



Limit Configuration

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command selects whether the limit switch inputs on the motor connector are ignored, otherwise it will stop motion.					
Returns:		A read operation is not available with this command.					
Syntax:		nLCGx – Standard syntax Error(s): LCGx – Missing axis number [30] nLCG – Missing program number parameter [28]					
Parameter Description:		n[int] – Axis number x[int] – 0 – ignore [default] 1 – active					
Parameter Range:		n – 1 to 99 x – 0 – ignore [default] 1 – Home uses Soft Limits 2 – Limits Switches Enabled 3 – Home Uses Soft Limits and Limit Switches enabled					
Related Commands:		LPL					
Example:		1LCG1 Axis 1, set limit switches active					

Positive/ Negative Limit Location

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		Determines orientation of Positive limit, and negative limit.					
Returns:		A read operation returns the following limit direction values for the specified axis: 0 – Normal orientation 1 – Reverse orientation					
Syntax:		nLDRx – Standard syntax nLDR? – Read velocity value 0LDRx – Missing axis number, all axes set limit direction Error [#]: LDR? – Read operation with missing axis number [27] nLDR – Missing limit parameter [28]					
Parameter Description:		n[int] – Axis number x[int] – limit direction value ? – Read limit direction value					
Parameter Range:		n – 0 to 99 x – 0 or 1					
Related Commands:							
Example:		1LDR1 Axis 1, set to reverse orientation – 5LDR? Axis 5, Read limit switch orientation					

Limit Status

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓		✓		✓
Command Description:		Returns the status of both limit switches in the form LSP, LSN. This is useful for limit switch configuration.					
Returns:		A read operation returns current limit status for the specified axis.					
Syntax:		nLIM? – Standard syntax Error [#]: LIM? – Read operation with missing axis number [123]					
Parameter Description:		n[int] – Axis number ? – Read limit switches					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		6LIM? Axis 6, read current limit status					

Lead Screw Pitch

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command sets the lead screw pitch.					
Returns:		A read operation returns the lead screw pitch value in mm for the specified axis.					
Syntax:		nLSPx – Standard syntax nLSP? – Read lead screw pitch value OLSPx – All axes set lead screw pitch to x Error [#]: LSP? – Read operation with missing axis number [27] nLSP – Missing pitch parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Lead Screw Pitch ? – Read Lead Screw Pitch					
Parameter Range:		n – 0 to 99 x – 1nm(.000001) to 999.999999mm					
Related Commands:							
Example:		1LSP.25 Axis 1, Set pitch to 0.25mm – 5LSP? Axis 5, Read Lead Screw Pitch					

LST

Program List

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
			✓				
Command Description:		This command is used to display the individual commands entered by the user to create the specified program. NOTE: Commands are returned sequentially and individually, which means in the Micronix GUI they will be listed from bottom (first returned) to top (last returned).					
Returns:		A read operation returns the program table for the specified axis.					
Syntax:		nLSTx – Standard syntax Error [#]: LSTx – Read operation with missing axis number [123]					
Parameter Description:		n[int] – Axis number x[int] – # program table to be read					
Parameter Range:		n – 1 to 99					
Related Commands:		PGM, ERA,					
Example:		6LST1 Axis 6, read program table for program 1					

LPL

Limit Switch Polarity

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command sets whether the limit switch inputs are active high[1] or low[0]					
Returns:		A read operation returns the program table for the specified axis.					
Syntax:		nLPLx – Standard syntax Error(s): LPLx – Missing axis number [30] nLPL – Missing limit polarity parameter [28]					
Parameter Description:		n[int] – Axis number x – 0 – Active Low – 1 – Active High					
Parameter Range:		n – 1 to 99 x – 0 – active low [default] 1 – active high					
Related Commands:		LCG					
Example:		6LPL1 Axis 6, limit switches set to active high					



Max Motor Current

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓			✓	
Command Description:		This command is used to read the maximum output current to the motor as determined by hardware. The MCS setting cannot exceed this value.					
Returns:		A read operation returns the max motor current value in Amps for the specified axis.					
Syntax:		nMCMx – Standard syntax nMCM? – Read max motor current value Error [#]: MCM? – Read operation with missing axis number [27] nMCM – Missing current parameter [28]					
Parameter Description:		n[int] – Axis number ? – Read max motor current value					
Related Commands:		MCS, MCR					
Example:		5MCM?		Axis 5, Read max motor current value			



Motor Current Setting

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command sets the desired current output level.					
Returns:		A read operation returns the Motor current value in Amps for the specified axis.					
Syntax:		nMCSx – Standard syntax nMCS? – Read Motor Current value 0MCSx – All axes set Motor Current Error [#]: MCS? – Read operation with missing axis number [27] nMCS – Missing current parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – motor current in Amps ? – Read current value					
Parameter Range:		n – 0 to 99 x – 0 to MCM (2A)					
Related Commands:		MCM					
Example:		1MCS .25 Axis 1, Set motor current to 0.25A – 5MCS? Axis 5, Read motor current value					



Move to Negative Limit

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command initiates a move to the negative limit position. An error will occur if there is no encoder signal at the time of execution. This command blocks all communication over the serial port during motion. The controller will buffer all commands sent during this period and execute them once the command has found the limit.					
Returns:		A read operation is not available with this command.					
Syntax:		nMLN – Standard syntax 0MLN – All axes execute move to negative limit position Error [#]: MLN – Missing axis number [30]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		MLP, LCG					
Example:		8MLN Axis 8, Move to negative limit position – 0MLN All Axes, Move to negative limit position					

MLP

Move to Positive Limit

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command initiates a move to the positive limit position. An error will occur if there is no encoder signal at the time of execution. This command blocks all communication over the serial port during motion. The controller will buffer all commands sent during this period and execute them once the command has found the limit.					
Returns:		A read operation is not available with this command.					
Syntax:		nMLP – Standard syntax 0MLP – All axes execute move to positive limit position Error [#]: MLP – Missing axis number [30]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		MLN, LCG					
Example:		1MLP Axis 1, Move to positive limit position – 0MLP All Axes, Move to positive limit position					



Toggle Motor Off/On

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to turn the motor current flow "Off" or "On" for a specified axis. Primarily used for stages utilizing stepper motors where the motor would be unable to rotate freely while powered.					
Returns:		A read operation returns the following motor current off/on values for the specified axis: 0 – Motor current is off 1 – Motor current is on					
Syntax:		nMOTx – Standard syntax nMOT? – Read motor current off/on value 0MOTx – All axes set motor value Error [#]: MOT? – Read operation with missing axis number [27] xMOT – Missing motor off/on parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Motor current off/on ? – Read motor current off/on value					
Parameter Range:		n – 0 to 99 x – 0 for motor current off 1 for motor current on					
Related Commands:		None					
Example:		1MOT0		Axis1, Set motor current to off			

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command set the motor polarity for the specified axis. If the theoretical positive direction is away from the motor, changing this setting will make the theoretical positive direction towards to motor.					
Returns:		A read operation returns the current motor polarity setting for the specified axis.					
Syntax:		nMPLx – Standard syntax nMPL? – Read Motor polarity value 0MPLx – All axes set motor polarity value Error [#]: MPL? – Read operation with missing axis number [27] nMPL – Missing motor polarity parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Motor Polarity setting ? – Read motor current off/on value					
Parameter Range:		n – 0 to 99 x – 0 Normal 1 Reverse					
Related Commands:		MVR					
Example:		1MPL0		Axis1, To normal Polarity			



Synchronous Move - Absolute

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command is used to set up a synchronous move using the absolute position of the axes involved. This command is most useful when coordinating motion to an absolute position between 2 or more axes and requires a RUN command on a separate line to execute the synchronous move. It is recommended to run multiple MSA commands on the same command line, as they are executed closer together than on separate lines. If the position is outside of the soft limits, the command will be ignored.					
Returns:		A read operation is not available with this command.					
Syntax:		nMSAx – Standard syntax 0MSAx – All axes setup synchronous move Error [#]: nMSA – Missing absolute position parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Absolute position					
Parameter Range:		n – 0 to 99 x – ± 0.000001 to 999.999999 mm (degrees)					
Related Commands:		RUN, MSR					
Example:		1MSA10;2MSA10 Axis 1, Move to absolute position: 10 mm[degrees]; Axis 2, Move to absolute position: 10 mm [degrees] 0RUN All axes, Execute synchronous move - 0MSA5 All axes, Move to absolute position: 5 mm [degrees] 0RUN All axes, Execute synchronous move					



Synchronous Move – Relative

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command is used to set up a relative move using the relative position of the axes involved. This command is most useful when coordinating relative positions between 2 or more axes and requires a RUN command on a separate line to execute the synchronous move. It is recommended to use multiple MSR commands on the same command line, as they are executed closer together than on separate lines. If the position is outside of the soft limits, the command will be ignored.					
Returns:		A read operation is not available with this command.					
Syntax:		nMSRx – Standard syntax 0MSRx – All axes setup synchronous move Error [#]: nMSR – Missing relative position parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Relative position					
Parameter Range:		n – 0 to 99 x – ± 0.000001 to 999.999999 mm (degrees)					
Related Commands:		RUN, MSA					
Example:		4MSR . 1 ; 5MSR . 5		Axis 4, Move 0.1 mm [degrees]; Axis 5, Move 0.5 mm [degrees]			
		0RUN		Execute synchronous move			
		-					
		0MSR0 . 01		All axes, Move 0.01 mm [degrees]			
		0RUN		All axes, execute synchronous move			



Move Absolute

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command is used to initiate an instantaneous move to an absolute position for a specified axis. If the position is outside of the soft limits, the command will be ignored.					
Returns:		A read operation is not available with this command.					
Syntax:		nMVAX – Standard syntax 0MVAX – All axes execute instantaneous move Error(s): nMVA – Missing absolute position parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Absolute position					
Parameter Range:		n – 0 to 99 x – -999.999999 to 999.999999 mm (degrees)					
Related Commands:		MVR, POS					
Example:		4MVA14.5 Axis 4, Move to absolute position: 14.5 mm [degrees] – 0MVA5.5 All axes, Move to absolute position: 5.5 mm [degrees]					



Move Relative

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command is used to initiate an instantaneous move to a relative position for a specified axis. If the position is outside of the soft limits, the command will be ignored.					
Returns:		A read operation is not available with this command.					
Syntax:		nMVRx – Standard syntax 0MVRx – All axes execute command. Error(s): nMVR – Missing relative position parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Relative position					
Parameter Range:		n – 0 to 99 x – ± 0.000001 to 999.999999 mm [degrees]					
Related Commands:		MVA, POS					
Example:		6MVR10 Axis 6, Move 10 mm [degrees] – 0MVR.89 All axes, Move 0.89 mm [degrees]					

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		<p>This command is used to change the number of times a program will execute. If the program loop setting is 0, any program that is executed will run in a continuous loop. It can be combined with the PGS command to run a program continuously on startup. To disable program looping, set PGL to 1. A looping program can be stopped at any time by sending the STP or EST commands.</p> <p>This version of the command available in firmware version 1.3.11 and up. Prior version have an on/off PGL setting 1/0.</p>					
Returns:		A read operation returns the program loop setting for the specified axis.					
Syntax:		<p>nPGLx – Standard syntax</p> <p>Error(s):</p> <p>PGLx – Missing axis number [30]</p> <p>nPGL – Missing program number parameter [28]</p>					
Parameter Description:		<p>n[int] – Axis number</p> <p>x[int] – loop flag parameter</p>					
Parameter Range:		<p>n – 1 to 99</p> <p>x – 0 – Loop indefinitely</p> <p>1 – Don't Loop</p> <p>2 to 999999 – number of times an executed command will repeated</p>					
Related Commands:		PGS, STP					
Example:		<p>1PGL0 Axis 1, Run program 1 continuously</p> <p>1PGL5 Axis 1, Run program 5 times</p>					



Begin Program Recording

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓				
Command Description:		This command is used to enter program recording mode for a specified axis. The program being recorded must use a unique program number or else the program will be ignored. Use the LST command to check program number availability and use the ERA command to erase any previously recorded programs. Each program has a size limit of 4Kb.					
Returns:		A read operation is not available for this command					
Syntax:		nPGMx – Standard syntax nPGM? – Read a binary representation of written program numbers If programs 1 and 2 are written it will return 3 If programs 1 and 4 are written it will return 9 If only program 1 is written it will return 1 If only program 3 is written it will return 4 Error(s): PGMx – Missing axis number [30] nPGM – Missing program number parameter [28]					
Parameter Description:		n[int] – Axis number x[int] – Program number to be recorded					
Parameter Range:		n – 1 to 99 x – 1 to 16					
Related Commands:		END, EXC, LST, ERA					
Example:		1 PGM3		Axis 1, Begin recording program. Save program as program 3			



Run Program At Start-Up

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set a program to run immediately on start-up. Only one program per axis can run on start-up.					
Returns:		A read operation returns a value for the specified axis in the format below: 0 – No program set to run 1-16 – Program set to run on start-up					
Syntax:		nPGSx – Standard syntax 0PGSx – Missing axis number, all axes set program to run on start-up nPGS? – Read program(s) set to run on start-up Error [#]: PGS? – Read operation with missing axis number [27] nPGS – Missing program set to run on start-up parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Program set to run on start-up ? – Read encoder mode value					
Parameter Range:		n – 0 to 99 x – 0 - No program 1 to 16- Specific program set to run on start-up					
Related Commands:		LST, PGM					
Example:		6PGS5 Axis 6, set program 5 to run on start-up – 0PGS23 All axes, set program 23 to run on start-up – 3PGS? Axis 3, Read program to run on start-up – 3PGS0 Axis 3, Set no program to run on start-up					

Set Feedback Constants

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command is used to set the encoder feedback constants for a specified controller.					
Returns:		A read operation returns the encoder feedback constant values for the specified axis.					
Syntax:		nPIDx1,x2,x3 – Standard syntax nPID? – Read encoder feedback constant values Error(s): PIDx1,x2,x3 – Missing axis number [30] PID? – Read operation with missing axis number [27] nPID – Missing encoder feedback constant parameters [28]					
Parameter Description:		n[int] – Axis number x1[float] – K_p (proportional term) x2[float] – K_i (integral term) x3[float] – K_d (derivative term) ? – Read encoder feedback constants and values					
Parameter Range:		n – 1 to 99 x1 – 0.000 to 1.000 x2 – 0.000 to 1.000 x3 – 0.000 to 1.000					
Related Commands:		FBK, ENC, POS					
Example:		5PID.02,.04,.05 Axis 5, Set encoder feedback constants to 0.02, 0.04 and 0.05, respectively – 2PID.03,, Axis 2, Set encoder feedback constant K_p to 0.03, other constants remain unchanged – 4PID,,.07 Axis 4, Set encoder feedback constant K_d to 0.07, other constants remain unchanged					

POS

Read Current Position

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command is used to read the position information from the specified axis controller					
Returns:		A read operation returns the position values in mm for the specified axis in the following format: [Theoretical position in mm; Encoder position in mm] [Theoretical position in degrees; Encoder position in degrees]					
Syntax:		nPOS? – Standard syntax Error(s): POS? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number ? – Read position values					
Parameter Range:		n – 1 to 99					
Related Commands:		MVR					
Example:		4POS? Axis 4, Read position values					

Set Resolution

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓			✓	
Command Description:		This command sets the system resolution. If CFG is 0 this value is calculated automatically based of LSP, FSR and GRR The units are (picometers/fullstep)/ 10.					
Returns:		A read operation returns the resolution value in (pico meters/fullstep)/10 for the specified axis.					
Syntax:		nREZx – Standard syntax nREZ? – Read (picometers/fullstep)/ 10 value Error(s): REZ? – Read operation with missing axis number [27] REZx – Missing axis number [30] nREZ – Missing (picometers/fullstep)/ 10 parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – (picometers/fullstep)/ 10 ? – Read (picometers/fullstep)/ 10					
Parameter Range:		n – 1 to 99 x – 0 to 0-2^32 (pico meter/fullstep)/ 10					
Related Commands:		None					
Example:		9REZ25 Axis 9, Set resolution to 25 (picometers/fullstep)/ 10 – 3REZ? Axis 3, Read (picometers/fullstep)/ 10 resolution value					

RST

Perform Soft Reset

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command is used to perform a soft reset of the specified axis.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nRST – Standard syntax ORST – All axes execute soft reset					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		8RST		Axis 8, execute soft reset			

RUN

Start Synchronous Move

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command is used to start a global synchronous move previously set up by using the MSA or MSR commands.					
Returns:		A read operation cannot be used with this command.					
Syntax:		RUN – Standard syntax					
Parameter Description:		-					
Parameter Range:		-					
Related Commands:		MSA, MSR					
Example:		3MSR5;4MSR5		Axis 3, Move 5 mm [degrees];			
		0RUN		Axis 4, Move 5 mm [degrees]			
				All axes, Execute synchronous move			

SAV

Save Axis Settings

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command is used to save all settings for the specified axis. This allows an axis to be configured on power up.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nSAV – Standard syntax 0SAV – All axes save settings					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		None					
Example:		16SAV		Axis 16, save settings			

During Motion		Real-time		Program		Global				
Set	Read	Set	Read	Set	Read	Set	Read			
	✓		✓							
Command Description:		This command is used to check the status register for a specified axis.								
Returns:		A read operation will return an integer from 0 to 255 describing the status of the axis. The byte must be decoded in binary to determine the value of each bit.								
		Bit	7	6	5	4	3	2	1	0
		Name	ERR	ACC	CNST	DEC	STP	PGM	PLS	NLS
		Note: Bits 2, 1 and 0 are unused								
		Bit 7:	1 – One or more errors have occurred. Use ERR? Or CER to clear. 0 – No Errors have occurred.							
		Bit 6:	1 – Currently in Acceleration phase of motion. 0 – Not in Acceleration phase of motion.							
		Bit 5:	1 – Currently in Constant Velocity phase of motion. 0 – Not in Constant Velocity phase of motion.							
		Bit 4:	1 – Currently in Deceleration phase of motion. 0 – Not in Deceleration phase of motion.							
		Bit 3:	1 – Stage has stopped. (In Closed Loop Stage, is in the deadband) 0 – Stage is moving. (In Closed Loop, Stage is out of deadband)							
		Bit 2:	1 – A Program is currently running 0 – No program is running							
Bit 1:	1 – Positive Switch is Activated 0 – Positive Switch is not Activated									
Bit 0:	1 – Negative Switch is Activated 0 – Negative Switch is not Activated									
Syntax:		nSTA? – Standard syntax Error(s): STA? – Read operation with missing axis number [27] nSTA – Missing read operation parameter [28]								
Parameter Description:		n[int] – Axis number ? – Read status register								
Parameter Range:		n – 1 to 99								
Related Commands:		None								
Example:		6STA? Axis 6, Read status register								

STP

Stop Motion

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
✓		✓				✓	
Command Description:		This command is used to stop motion for a specified axis.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nSTP – Standard syntax OSTP – All axes execute stop					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		EST, DEC					
Example:		8STP Axis 4, execute stop					

SVP

Save Startup Position

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the startup position. Default is 0. This setting does not require the SAV command to save it into memory. It also does not change with a DEF command. To reset the Startup position to the default, send nSVP0.					
Returns:		A read operation returns the Startup position setting for the specified axis.					
Syntax:		nSVP – Standard syntax 0SVP – Missing axis number, command accepted as standard syntax					
Parameter Description:		n[int] – Axis number x[float] – Startup Position mm ? – Read Startup Position					
Parameter Range:		n – 0 to 99 x – TLN (-999.999999mm) to TLP(999.999999mm)					
Related Commands:		None					
Example:		4SVP Set current position to Startup position 2SVP2.3 Set startup position to 2.3mm					

SYN

Sync

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
				✓		✓	
Command Description:		This command is used in a program together with the wait for sync [WSY] command in order to synchronize motion between multiple axes.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nSYN – Standard syntax 0SYN – Missing axis number, command accepted as standard syntax					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 0 to 99					
Related Commands:		None					
Example:		4SYN Send sync to axis 4					

TLN

Negative Soft Limit Position

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the desired negative soft limit position, using absolute position, for the specified axis. The negative soft limit position value must be less than the positive soft limit position value [TLP] for the command to be accepted.					
Returns:		A read operation returns the negative soft limit position value.					
Syntax:		nTLNx – Standard syntax nTLN? – Read negative soft limit position value 0TLNx – All axes set limit position value nTLN – Set current position to negative limit Error(s): TLN? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number x[float] – Negative soft limit position ? – Read negative soft limit position					
Parameter Range:		n – 0 to 99 x – -999.999999 to TLP mm [degrees]					
Related Commands:		TLP					
Example:		2TLN0.005 Axis 2, Set negative soft limit position to 0.005 mm [degrees] – 6TLN? Axis 6, Read negative soft limit position value					

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the desired positive soft limit position, using absolute position, for the specified axis. The positive soft limit position value must be greater than the negative soft limit position value [TLN] for the command to be accepted.					
Returns:		A read operation returns the positive soft limit position value for the specified axis.					
Syntax:		nTLPx – Standard syntax nTLP? – Read positive soft limit position value 0TLPx – All axes set limit position value nTLN – Set current position to negative limit Error(s): TLP? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number x[float] – Positive soft limit position ? – Read positive soft limit position					
Parameter Range:		n – 0 to 99 x – TLN to 999.999999 mm [degrees]					
Related Commands:		TLN					
Example:		4TLP10.005 Axis 2, Set positive soft limit position to 10.005 mm [degrees] – 9TLP? Axis 9, Read positive soft limit position value					

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command is used to execute a trace of the specified axis.					
Returns:		A read operation returns the position samples taken for the specified axis.					
Syntax:		nTRAx1,x2,x3 – Standard syntax nTRA? – Read position values OTLPx1,x2,x3 – All axes execute trace Error(s): TRA? – Read operation with missing axis number [27] nTRA – Missing parameters [28]					
Parameter Description:		n[int] – Axis number x1[int] – Number of samples taken (default is 1000) x2[int] – 10kHz /Sampling frequency (default is 1) x3[float] – Trace starting position (default is immediate) ? – Read position					
Parameter Range:		n – 0 to 99 x1 – 1 to 9000 x2 – 1 to 1000 Servo clocks per cycle x3 – 000.000000 to 999.999999 mm [degrees]					
Related Commands:		DAT					
Example:		5TRA5,10,1 Axis 5, execute trace with 5 samples at a sampling frequency of 1kHz starting at a position of 1 mm [degrees] 3TRA2000,, Axis 3, execute trace with 2000 samples at a sampling frequency of 10kHz starting at the current position					



Max Microsteps

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		Query only. Returns the max number of microsteps achievable based on the motor current setting.					
Returns:		A read operation returns the maximum possible microsteps for the specified axis.					
Syntax:		nUMXx – Standard syntax nUMX? – Read Max Microsteps value Error [#]: UMX? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number ? – Read velocity value					
Parameter Range:		n – 0 to 99					
Related Commands:							
Example:		5UMX? Axis 5, Read Maximum microsteps					

Microsteps

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓	✓	✓	✓		✓	
Command Description:		This command sets the current Microstepping value. Max determined by UMX. 4096 at full current.					
Returns:		A read operation returns the microstepping value for the specified axis.					
Syntax:		nUSTx – Standard syntax nUST? – Read microstepping rate 0USTx – Missing axis number, all axes set to x microstepping Error [#]: UST? – Read operation with missing axis number [27] nUST – Missing microstep parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Microsteps ? – Read microstep value					
Parameter Range:		n – 0 to 99 x – 1 to UMX (4096)					
Related Commands:		UMX					
Example:		1UST2000 Axis 1, Set 2000 microsteps [degrees/s] – 5UST? Axis 5, Read microstep value					

VEL

Velocity

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
✓	✓	✓	✓	✓		✓	
Command Description:		This command is used to set the desired velocity for the specified axis. The velocity may be changed on-the-fly by sending another VEL command during motion. The velocity value should be lower than the maximum allowable velocity [VMX] for the command to be accepted.					
Returns:		A read operation returns the velocity value in mm/s for the specified axis.					
Syntax:		nVELx – Standard syntax nVEL? – Read velocity value 0VELx – Missing axis number, all axes set velocity Error [#]: VEL? – Read operation with missing axis number [27] nVEL – Missing velocity parameter [28]					
Parameter Description:		n[int] – Axis number x[float] – Velocity value ? – Read velocity value					
Parameter Range:		n – 0 to 99 x – 000.001 to VMX (999.999 mm/s) [degrees/s] – 0 to set VEL to VMX					
Related Commands:		VMX, REZ					
Example:		1VEL.25 Axis 1, Set velocity to 0.25mm/s [degrees/s] – 5VEL? Axis 5, Read velocity value					

VER

Firmware Version

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command is used to check the firmware version for the specified axis.					
Returns:		A read operation returns the firmware version for the specified axis.					
Syntax:		nVER? – Standard syntax Error(s): VER? – Read operation with missing axis number [27] nVER – Missing read operation parameter [28]					
Parameter Description:		n[int] – Axis number ? – Read firmware version					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		11VER? Axis 11, Read firmware version					



Maximum Allowable Velocity

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command is used to read the maximum allowable velocity for a specific axis. This value is calculated based on the steps per micron parameter in the REZ command.					
Returns:		A read operation returns the maximum allowable velocity value in mm/s for the specified axis.					
Syntax:		nVMX? – Read maximum allowable velocity value Error [#]: VMX? – Read operation with missing axis number [27] nVMX – Missing read operation parameter [123]					
Parameter Description:		n[int] – Axis number ? – Read maximum allowable velocity value					
Parameter Range:		n – 1 to 99					
Related Commands:		REZ, VEL					
Example:		4VMX? Axis 4, Read maximum allowable velocity value					

VRT

Encoder Velocity

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
	✓		✓				
Command Description:		This command returns the actual velocity calculated from the encoder.					
Returns:		A read operation returns the encoder velocity in mm/s.					
Syntax:		nVRT? – Standard syntax Error [#]: VRT? – Read operation with missing axis number [27]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		POS					
Example:		5VRT?		Axis 5, Read encoder velocity			

WST

Wait For Stop

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
				✓			
Command Description:		This command is used in a program to wait until motion is completed to begin executing the next command.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nWST – Standard syntax WST – Missing axis number, command accepted as standard syntax					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		7WST		Axis 7, Wait for motion to stop before executing next command			

WSY

Wait For Sync

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
				✓		✓	
Command Description:		This command is used in a program together with the sync [SYN] command in order to synchronize motion between multiple axes.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nWSY – Standard syntax WSY – Missing axis number, command accepted as standard syntax					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		1WSY		Axis 1, Wait until sync command is received before executing next command			



Wait For Time Period

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
				✓			
Command Description:		This command is used in a program to wait for a specified period of time before executing the next command.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nWTMx – Standard syntax WSTx – Missing axis number, command accepted as standard syntax					
Parameter Description:		n[int] – Axis number x[int] – Time					
Parameter Range:		n – 1 to 99 x – 0 to 999999 milliseconds					
Related Commands:		None					
Example:		2WTM42		Axis 2, Wait for 42 milliseconds before executing next command			



Zero Position

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓		✓		✓	
Command Description:		This command is used to set the absolute zero position for the specified axis.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nZRO – Standard syntax Error [#]: ZRO – Missing axis number [123]					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:		1ZRO Axis 1, set current position as absolute zero					

ZZZ**Take Axis Offline**

During Motion		Real-time		Program		Global	
Set	Read	Set	Read	Set	Read	Set	Read
		✓				✓	
Command Description:		This command is used to take the specified axes offline. An offline axis will not respond until the power is cycled.					
Returns:		A read operation cannot be used with this command.					
Syntax:		nZZZ – Standard syntax ZZZ – Missing axis number, all axes set to offline					
Parameter Description:		n[int] – Axis number					
Parameter Range:		n – 1 to 99					
Related Commands:		None					
Example:							

5.9 Error Messages

Error Number	Name	Description
10	Receive Buffer Overrun	The Receive Buffer has reached or exceeded maximum capacity.
11	Motor Disabled	The command that triggered this error was trying to move the servo while it was disabled.
12	No Encoder Detected	The command that triggered this error was trying to access encoder data when no encoder was attached.
13	Index Not Found	The controller moved across the full range of motion and did not find an index.
14	Home Requires Encoder	The HOM command requires an encoder signal.
15	Move Limit Requires Encoder	The MLN and MLP commands require an encoder signal.
20	Command is Read Only	The command that triggered this error only supports read operations. The command must be followed by a question mark to be accepted. Ex: XXX?
21	One Read Operation Per Line	Multiple read operations on the same command line. Only one read operation is allowed per line, even if addressed to separate axes.
22	Too Many Commands On Line	The maximum number of allowed commands per command line has been exceeded. No more than 8 commands are allowed on a single command line.
23	Line Character Limit Exceeded	The maximum number of characters per command line has been exceeded. Each line has an 80 character limit.
24	Missing Axis Number	The controller could not find an axis number or the beginning of an instruction. Check the beginning of the command for erroneous characters.
25	Malformed Command	The controller could not find a 3-letter instruction in the input. Check to ensure that each instruction in the line has exactly 3 letters referring to a command.
26	Invalid Command	The 3-letter instruction entered is not a valid command. Ensure that the 3-letter instruction is a recognizable command.

27	Global Read Operation Request	A read request for a command was entered without an axis number. A read request cannot be used in a global context.
28	Invalid Parameter Type	<p>1. The parameter entered does not correspond to the type of number that the instruction requires. For example, the command may expect an integer value, therefore sending a floating point value will trigger this error.</p> <p>2. The allowable precision for a parameter has been exceeded. For example, velocity can be specified with a precision of 0.001 mm/sec. If a more precise velocity value of 0.0001 mm/sec is entered, this error will be triggered. Refer to the command pages for the type of parameter that each command expects.</p>
29	Invalid Character in Parameter	There is an alpha character in a parameter that should be a numeric character.
30	Command Cannot Be Used In Global Context	The command entered must be addressed to a specific axis number. Not all commands can be used in a global context. Check the specific command page or the table of commands for more info.
31	Parameter Out Of Bounds	The parameter is out of bounds. The current state of the controller will not allow this parameter to be used. Check the command page for more information.
32	Incorrect Jog Velocity Request	The jog velocity can only be changed during motion by using a new JOG command. If the VEL command is used to change the velocity, this error will be triggered. The VEL command can only be used to change velocity during motion initiated by the move commands [MVR, MVA, MSR, MSA].
33	Not In Jog Mode	Sending a JOG command during motion initiated by a move command will trigger this error. To initiate Jog Mode, the controller should be at stand-still. To change velocity during a move, use the VEL command.
34	Trace Already In Progress	This error is triggered when a new trace command is received after a trace is already in progress. Trace settings may be modified only if the trace hasn't started recording data. Otherwise, wait until the trace has finished before modifying the trace settings.
35	Trace Did Not Complete	An error occurred while recording trace data. Try the operation again.
36	Command Cannot Be Executed During Motion	Only certain commands can be executed when motion is in progress. Check the command pages for information on individual commands.
37	Move Outside Soft Limits	If a requested move will take the controller outside of the preset travel limits, then the command will not be executed.

38	Read Not Available For This Command	This error is triggered by a read request from a command that does not support a read operation.
39	Program Number Out of Range	The number entered for the program number was either less than 1 or greater than 16.
40	Program Size Limit Exceeded	The program has exceeded the character limit of 4 Kb.
41	Program failed to Record	Error in recording program. Erase program and try operation again.
42	End Command Must Be on its Own Line	The End command used to end a program must be on a separate line from all other instructions.
43	Failed to Read Program	An error occurred while trying to read a program. Try the Operation again.
44	Command Only Valid Within Program	The command that triggered this error is only suitable for use within a program.
45	Program Already Exists	A program already exists for the indicated program parameter. The program must be erased with the ERA command before being written again.
46	Program Doesn't Exist	The indicated program does not exist. This error can occur when you try to execute a program number that has not had a program assigned to it.
47	Read Operations Not Allowed Inside Program	Read Operations are not permitted in programs.
48	Command Not Allowed While Program in Progress	The command that triggered this error was given while a program was executing.
50	Limit Activated	Motion in the direction of the activated limit switch is disallowed if limit switches are enabled.
51	End of Travel Limit	The requested move will take the controller outside of its valid travel range, therefore the move is disallowed.
52	Home In Progress	A Home or a Move To Limit Procedure is in progress. Motion commands are disallowed during this time. A STP or EST command can be used to terminate the Home, and then a motion command can be sent.
53	IO Function Already In Use	The I/O Function in question is already assigned to another I/O pin. Some Functions can only be assigned to one pin at a time. See the documentation for each function for more details.

54	Invalid Resolution	The parameters entered for Gear Ratio, Lead-Screw Pitch, and Full Steps Per Revolution result in a resolution that cannot be handled by the controller.
55	Limits Are Not Configured Properly	Both Limit Switches are active, so motion is disallowed in both directions. Most likely the LPL(Limit Polarity command) setting should be switched.
80	Command Not Available in this Version	The command entered is not supported in this version of the firmware.
81	Analog Encoder Not Available In this Version	The current version of firmware installed does not support Analog Encoders.

6. Appendix

6.1 Encoder Input Pin-out

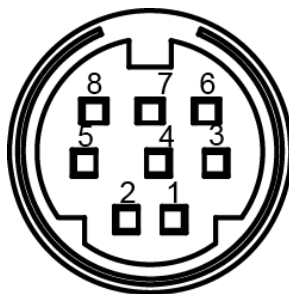
Pin	Description
1	A+/Cos+
2	B+/Sin+
3	Index +
4	Ground
5	+5V
6	A-/Cos-
7	B-/Sin-
8	Index -
9	Not In Use

6.2 Motor Pin-out

Pin	Description
1	Phase A+
2	Phase A-
3	Phase B+
4	Phase B-
5	Ground
6	LSN
7	LSP
8	+5V
9	Ground

6.3 8-Pin Din IO connector

Pin8 - +5V
Pin6 - IO1 (output only)
Pin5 - IO2
Pin3 - IO3
Pin2 - IO4
Pin4 - GND

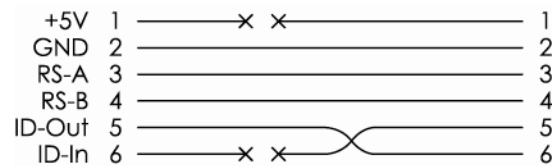


I/O ports can be set up as either active high or active low,
With a recommended input current of 5mA and a maximum output current of 50mA.

6.4 RS-485 Intermodular Connector Cable Pin-out

The RS-485 Intermodular Connector Cable is used to daisy chain two MMC modules together, allowing for alternative module configurations. The cable is directional and its orientation should be noted when configuring axis numbers, for the direction of the cable will determine axis order. This connector can also be used to communicate with the controller in place of the USB connection by connecting your RS-485 Bus to pins 2, 3 and 4 as they appear below.

RS-485 Intermodular Connector Cable Pin-out:



6.5 Firmware

The firmware on the MMC-200 can be updated without returning the controller to manufacturer. For questions regarding the current firmware release and updating the firmware of your MMC-200 Please contact Micronix USA support. Please be sure to check the firmware version by using the VER command.