

README

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November 20, 2014

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1 Actuator Position Control via EtherNet/IP

The `cpppo_positioner` module allows control of the position of a set of actuators, by initiating a communication channel, and issuing new position directives via the actuator state machine. The current state is polled as necessary via EtherNet/IP CIP read commands, and data updates and state changes are performed via EtherNet/IP CIP writes.

1.1 Installing

Clone the repository, and run the `setup.py` installer:

```
$ git clone git@github.com:pjkundert/cpppo_positioner.git
$ cd cpppo_positioner
$ python setup.py install
$ python
Python 2.7.6 (default, Sep  9 2014, 15:04:36)
[GCC 4.2.1 Compatible Apple LLVM 6.0 (clang-600.0.39)] on darwin
Type "help", "copyright", "credits" or "license" for more information.
>>> import cpppo_positioner
>>>
```

1.2 Command- or Pipe-line usage

An executable module entry point (`python -m cpppo_positioner`), and a convenience executable script (`cpppo_positioner`) are supplied.

If your application generates a stream of actuator position data, or if you have some manual positions you wish to move to, you can use the command-line interface. You may supply one or more actuator positions in blobs of JSON data (an actual position would have more entries, such as `acceleration`, `deceleration`, `timeout`, ...):

```
$ position='{ "actuator": 0, "position": 12345, "speed": 100 }'
```

These positions may be supplied either as single parameters on the command line, or as separate lines of input (if standard input is selected, by supplying a `-` option):

```
$ python -m cpppo_positioner --address gateway -v "$position"
$ echo "$position" | cpppo_positioner --address gateway -v -
```