

# Hart Slave Stack C++ 8.0E

## Technical Data Sheet



C++ Source Code for an Embedded Firmware Module with the following Properties

- No external dynamic memory management. The amount of reserved RAM remains constant.
- The number of objects is determined at compile time and startup.
- No operating system is required to integrate the software. Timer and serial interrupts are enough.
- Simple asynchronous user interface to encapsulate the time-critical part.
- Implements the Uart protocol and Hart Ip.

The implementation is based on the Hart Documents in:  
HART Communication Protocol Specification, HCF\_SPEC-13, FCG TS20013 Revision 7.09,  
Release Date: 06 January 2023

Details for the Hart Protocol are provided via the following link:  
<https://www.fieldcommgroup.org/technologies/hart>.

<b>Hart Slave Stack C++ 8.0E</b>	<b>1</b>
<b>Introduction</b>	<b>2</b>
Implemented Commands	2
Architecture	3
<b>Hart Slave C++ Code</b>	<b>4</b>
User Interface	4
Public Functions	4
Data Interface	6
Coding Considerations	6
Hardware Abstraction	7
List of Files	7
System Requirements	8
Coding Conventions	9
<b>Visual Studio 2022</b>	<b>9</b>
Test Environment	9
Prerequisites	9
Development Directory Structure	9
Project Structure	10
Getting Started	10
Test Interface	11
<b>Appendix</b>	<b>14</b>
Internet Links	14
Download Location	14
Legal Issues	15
Conformity	15
Copyright	15
No Warranty	15

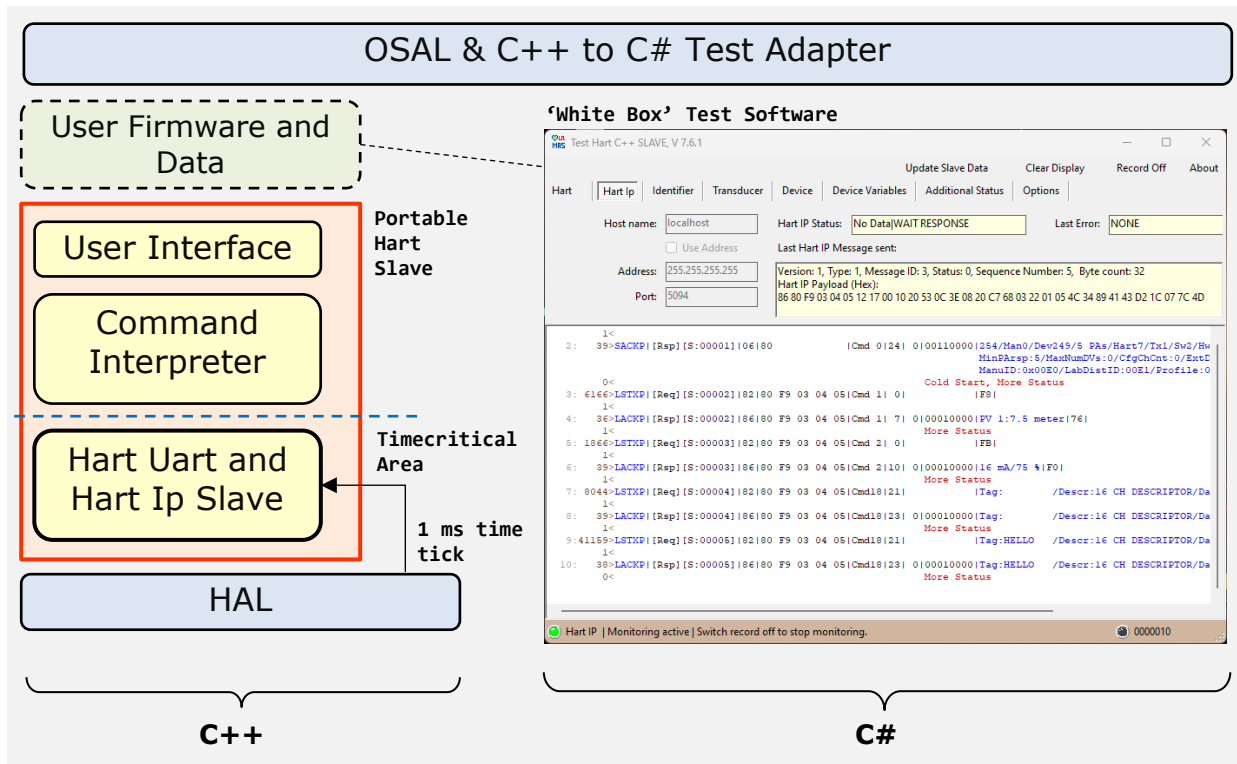
# Introduction

## Implemented Commands

#	Description	Remarks
Universal Commands		
0	Read Unique Identifier	See also Command Summary Specification
1	Read Primary Variable	
2	Read Loop Current And Percent Of Range	
3	Read Dynamic Variables And Loop Current	
6	Write Polling Address	
7	Read Loop Configuration	
8	Read Dynamic Variable Classifications	Currently only the standard device variables are supported: 244, 245, 246, 247, 248, 249, 0, 1, 2, 3.
9	Read Device Variables with Status	
11	Read Unique Identifier Associated With Tag	
12	Read Message	
13	Read Tag, Descriptor, Date	
14	Read Primary Variable Transducer Information	
15	Read Device Information	
16	Read Final Assembly Number	
17	Write Message	
18	Write Tag, Descriptor, Date	
19	Write Final Assembly Number	
20	Read Long Tag	
21	Read Unique Identifier Associated With Long Tag	
22	Write Long Tag	
38	Reset Configuration Change Flag	
48	Read Additional Device Status	The slave module saves a copy of the last additional device status sent for each master and compares it with the bitstream provided by the user application.
Common Practice Commands		
33	Read Device Variables	
34	Write Primary Variable Damping Value	
35	Write Primary Variable Range Values	
49	Write Primary Variable Transducer Serial Number	
54	Read Device Variable Information	Currently only the standard device variables are supported: 244, 245, 246, 247, 248, 249, 0, 1, 2, 3. Commands 1, 2, 3 and 9 are currently accepted. Burst messages are not (yet) supported.
108	Write Burst Mode Command Number	
109	Burst Mode Control	
512	Read Country Code	
513	Write Country Code	

I consider the now implemented set of commands to be the minimum that must be available in a Hart slave. However, I also recommend making all important functions of a slave accessible via universal and common practice commands and not using user-specific commands. In this case it is not necessary to provide a device description. This saves development time and development costs.

# Architecture



The package Portable Hart Slave includes all sources needed to represent the slave part of the Hart protocol. The package is written in standard C++ and does not use any direct connection to a system environment. Data link layer, application layer (command interpreter) and network management of the Hart protocol are implemented. The connection to the outside occurs via three interfaces: The User Interface, a Time Trigger and the HAL to the Uart interface.

I used the C# environment to debug the Hart slave code during development. In fact, it is not(!) a simulation that is used here. The firmware is simply embedded in a Windows environment that allows the code to run in real time(!). In this way, all functions of the implementation can be analyzed in detail. The analysis of the temporal processes takes place in the range of milliseconds.

The C# software (White Box Test) was developed to create a transparent user interface for visualizing the data and communication processes. Visual Studio 2022 and .NET 6.0 were used to keep the programming effort within limits.

The command interpreter is triggered from the C# environment, but this happens within a 'real' thread and not within a worker thread from .NET:

```
CommandInterpreter = new Thread(ExecuteCommandInterpreter);  
CommandInterpreter.Priority = ThreadPriority.Highest;  
CommandInterpreter.Start();
```

and in endless loop of the thread:

```
result = (EN_Bool)HartSlaveDLL.BAHASL_WasCommandReceived();  
if (result == EN_Bool.TRUE8)  
{  
    // Simulate typical application  
    Thread.Sleep(20);  
    command = HartSlaveDLL.BAHASL_ExecuteCommandInterpreter();  
}
```

# Hart Slave C++ Code

## User Interface

### Public Functions

The following functions are realized in the module HartS\_UartIface.cpp in the class **CUartSlave**. In the DLL interface for the test client the function names are preceded by BAHASL\_.

Declaration	Description
<b>Operation</b>	
<b>EN_Bool</b> OpenChannel( TY_Word port_number_, EN_CommType type_);	The function allocates the selected com port if possible and starts its own working thread for accessing the Hart services. The port_number_ is limited to the range of 1 .. 254. The selected communication type (type_) should be UART in this version of the paket. The function returns TRUE8 if successful. In the present implementation only a single channel is possible. Thus no channel handle is required.
<b>void</b> CloseChannel();	It is required to call this function at least when the application is terminating.
<b>Data Interface</b>	
<b>void</b> GetConstDataHart( TY_ConstDataHart* const_data_);	Copies constant data from the Hart slave area to the test application area.
<b>void</b> SetConstDataHart( TY_ConstDataHart* const_data_);	Copies constant data from the application area to the Hart slave area.
<b>void</b> GetDynDataHart( TY_DynDataHart* dyn_data_);	Copies dynamic data from the Hart slave area to the test application area.
<b>void</b> SetDynDataHart( TY_DynDataHart* dyn_data_);	Copies dynamic data from the application area to the Hart slave area.
<b>void</b> GetStatDataHart( TY_StatDataHart* stat_data_);	Copies static data from the Hart slave area to the test application area.
<b>void</b> SetStatDataHart ( TY_StatDataHart* stat_data_);	Copies static data from the application area to the Hart slave area.
<b>Command Interpreter</b>	
<b>EN_Bool</b> WasCommandReceived();	The function returns FB_Bool::TRUE8 if the Hart protocol has recently (a few milliseconds ago) received a command.
<b>TY_Word</b> ExecuteCommandInterpreter();	This function calls the command interpreter in the slave to process any new data. If the command was recognized and executed, the function returns the number of the command. If this was not the case, the value 0xffff is returned.
<b>Encoding</b>	
<b>void</b> PutInt8( TY_Byte data_, TY_Byte offset_, TY_Byte* data_ref_);	Insert an integer 8 into the byte array buffer pointed to by data_ref_ starting at the position offset_.
<b>void</b> PutInt16( TY_Word data_, TY_Byte offset_, TY_Byte* data_ref_, EN_Endian endian_);	Insert an integer 16 into the byte array buffer pointed to by data_ref_ starting at the position offset_. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.

## Technical Data Sheet

<pre>void PutInt24(     TY_DWord data_,     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Insert an integer 24 into the byte array buffer pointed to by data_ref_ starting at the position offset_. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PutInt32(     TY_DWord data_,     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Insert an integer 32 into the byte array buffer pointed to by data_ref_ starting at the position offset_. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PutInt64(     TY_DWord data_,     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Insert an integer 64 into the byte array buffer pointed to by data_ref_ starting at the position offset_. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PutFloat(     TY_Float data_,     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Insert a single precision IEEE 754 float value into the byte array buffer pointed to by data_ref_ starting at the position offset. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PutDFloat(     TY_DFloat data_,     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Insert a double precision IEEE 754 float value into the byte array buffer pointed to by dataRef starting at the position offset. Start with the most significant byte if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PutPackedASCII(     TY_Byte* asc_string_ref_,     TY_Byte asc_string_len_,     TY_Byte offset_,     TY_Byte* data_ref_);</pre>	Insert a string (asc_string_ref_) of the length of asc_string_len_ in packed ASCII format into the byte array buffer pointed to by data_ref_ starting at the position offset_. It is recommended that asc_string_len_ is an ordinary multiple of 4.
<pre>void PutOctets(     TY_Byte* stream_ref_,     TY_Byte stream_len_,     TY_Byte offset_,     TY_Byte* data_ref_);</pre>	Copy a number of stream_len_ bytes into the byte array buffer pointed to by data_ref_ starting at the position offset_.
<pre>void PutString(     TY_Byte* string_ref_,     TY_Byte string_max_len_,     TY_Byte offset_,     TY_Byte* data_ref_);</pre>	Copy a string from string_ref_ to data_ref_. The actual number of characters stored cannot be greater than string_max_len_. If the string contains a null, the last character saved is a null character if this does not exceed the string_max_len_ limit.
<b>Decoding</b>	
<pre>TY_Byte PickInt8(     TY_Byte offset_,     TY_Byte* data_ref_);</pre>	Return the value of the byte in the byte array buffer pointed to by data_ref_ from the position offset_.
<pre>TY_Word PickInt16(     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the integer 16 from the byte array buffer pointed to by data_ref_ from the position offset_. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.
<pre>TY_DWord PickInt24(     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the integer 24 from the byte array buffer pointed to by dataRef at the position offset. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.
<pre>TY_DWord PickInt32(     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the integer 32 from the byte array buffer pointed to by data_ref_ from the position offset_. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.
<pre>TY_UInt64 PickInt64(     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the integer 64 from the byte array buffer pointed to by data_ref_ from the position offset_. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.
<pre>TY_Float PickFloat(     TY_Byte offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the single precision IEEE754 number from the byte array buffer pointed to by data_ref_ from the position offset_. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.

## Technical Data Sheet

<pre>TY_DFloat PickDFloat(     TY_Byte  offset_,     TY_Byte* data_ref_,     EN_Endian endian_);</pre>	Return the value of the double precision IEEE754 number from the byte array buffer pointed to by data_ref_ from the position offset_. Assume that the most significant byte is the first if endian is MSB_FIRST(0), which is the Hart standard.
<pre>void PickPackedASCII(     TY_Byte* string_ref_,     TY_Byte  string_len_,     TY_Byte  offset_,     TY_Byte* data_ref_);</pre>	Generate a string and copy it to the buffer pointed to by sb. The final string should have the length string_len_. The packedASCII source is a set of bytes in the byte array buffer pointed to by data_ref_, starting at index offset_. Note: The string length has to be a multiple of 4 while the number of packedASCII bytes is a multiple of 3.
<pre>void PickOctets(     TY_Byte* stream_ref_,     TY_Byte  stream_len_,     TY_Byte  offset_,     TY_Byte* data_ref_);</pre>	Copy a number (numOctets) of bytes from the byte array buffer pointed to by dataSource to the user buffer pointed to by dataDestination.
<pre>void PickString(     TY_Byte* string_ref_,     TY_Byte  string_max_len_,     TY_Byte  offset_,     TY_Byte* data_ref_);</pre>	The function reads a string from a buffer (data_ref_) starting at index offset_ and stores the characters in string_ref_. The string buffer is read from until a null character appears or string_max_len_ is reached. If possible, the null character is also saved.
<b>Internal</b>	
<pre>void FastCyclicHandler(TY_Word time_ms_);</pre>	Although this function is not accessible to the test client, it is required for the operation of the Hart protocol. The function must be called by a separate task approximately every millisecond to enable timing in the communication. The time_ms parameter indicates how many milliseconds have passed since the last call. Usually this should be a value of 1 in most cases.

## Data Interface

The data interface provides three different types of data that can be written or read by the user. A structure is provided for each data type, which can be found in the file WbHartS\_Structures.h.

**Constant data** does not change. In most systems it is stored in flash memory and cannot be written.

**Dynamic data** is data that can always change. This includes measured values and status information.

**Static data** is used to configure a device. It is usually changed by external access. Whenever static data is changed, the configuration change flag must be set in Hart and the configuration change counter in Hart must be incremented.

## Coding Considerations

Microcontrollers which are used today for HART devices are at least 16 Bit microcontrollers. Otherwise the complexity of the measurement and number of parameters could not be managed.

☞ Low amount of memory.

The amount of memory is always critical because software kind of behaves like an ideal gas. It uses to fill the given space. Nevertheless, the coding of the Hart Slave was done as carefully as possible regarding the amount of flash memory and RAM.

☞ The user needs source code.

The Hart Protocol requires a strict timing specially for burst mode support and the primary and secondary master time slots. To provide the optimum transparency to the user to allow all kinds of debugging and to give the opportunity to optimize code in critical sections, the Hart Slave Firmware is not realized as a library but delivered as source code.

## Hardware Abstraction

☞ OSAL is including the HAL.

A Hardware Abstraction Layer is needed to design the interface of a software component independent from the hardware platform. In this very small interface of the Hart master a distinction of HAL and OSAL was not made. Therefore only an Operating System Abstraction Layer is defined which is covering all the needs of an appropriate HAL.

## List of Files

Category	Name	Description
<b>02-Code</b>		
01-Common	<b>OSAL.h</b>	The Operating System Abstraction Layer is the top header. This is where the central connection to the respective hardware or software platform takes place. The header OSAL.h can only exist once, while a special implementation (OSAL.cpp) exists for each specific hardware or software.
	<b>HartCoding.cpp/h</b>	This module combines functions that carry out the encoding and decoding of communication primitives and data objects.
	<b>HartFrame.cpp/h</b>	The hart frame is a construct used to collect all information which is needed to encode and decode data of so called service primitives like responses and requests, which are finally octet streams.
	<b>HartLib.h</b>	Some classes for the definition of HART constants.
<b>02-Code\01-Common</b>		
01-Interface	<b>HartSlaveIface.cpp/h</b>	This is where the actual interface of the master implementation is located, which would also have to be integrated into an embedded system. The version with the DLL is only intended for testing under Windows. You can find a detailed description of the provided functions in the 'Public Functions' chapter.
	<b>WbHartS_Structures.h</b>	This file contains structures which are accessed at the outer interface as well as in some modules in the master kernel.
	<b>WbHartS_TypeDefs.h</b>	This file contains type definitions which are used in all modules in the Hart master kernel.
	<b>WbHartUser.h</b>	Limits applied by the user of the hart master software.
	<b>HartDevice.cpp/h</b>	This module is nearly empty and subject to be removed.
02-AppLayer	<b>HartChannel.cpp/h</b>	The channel manages a communication interface and the associated properties. The channel also uses services to conduct Hart commands.
	<b>HartBurst.cpp/h</b>	Handling of the burst mode from the perspective of the application.
	<b>AnyCommandIntp.cpp/h</b>	Any command interpreter for common practice and user commands.
03-Layer7	<b>HartService.cpp/h</b>	In simple terms, a service executes a Hart command by passing a request to Layer2 of the Hart protocol. In doing so, it returns a handle to the caller, with which the calling program can check the status. A service is only considered completed when the caller has read the response (e.g. FetchConfirmation).
	<b>HartData.cpp/h</b>	Data defined for the Hart commands.
	<b>UniCommandIntp.cpp/h</b>	Universal commands interpreter.



## Technical Data Sheet

04-Layer2 01-Uart 02-HartIp	HSuartLayer2.cpp/h and HSipLayer2.cpp/h	This module implements the entire state machine of the Hart communication protocol (CHartSM) including the state machines for sending (CTxSM) and receiving (CRxSM) bytes.
	HSuartMacPort.h and HSipMacPort.h	The interface to the MAC port is relatively narrow and can be defined generically. However, the implementation depends on the hardware and software environment. That's why there is only a header at this point, while the files HMuartMacPort.cpp and HMipMacPort.cpp can be found in the OSAL area.
	HSuartProtocol.cpp/h and HSipProtocol.cpp/h	This protocol layer controls the UART interface on the lower level and calls the higher status machines when necessary (events). After this call, a ToDo Part occurs, which in turn affects the Uart or HartIp interface.
	Monitor.h	The same applies to the Monitor function as to the MacPort. At this point only the interface can be defined. The implementation takes place in the specific part.
<b>02-Code\02-Specific\01-WinDLL</b>		
01-Shell	BaHartSlave.cpp/h	The implementation for the calls to the Windows DLL is located here. In practice, it is just a shell through which the functions in the CUartMaster module are called.
02-OSAL 01-Uart 02-HartIp	HSuartMacPort.cpp and HSipMacPort.cpp	The Execute method is called directly by the fast cyclic handler. This basically drives all status machines in the Hart implementation. Here too, the method is divided into an Event handler and a ToDo handler.
	Monitor.cpp	On the one hand, there are methods that are mapped to the interface of the Windows DLL. In addition, there are a number of functions that are included with the kernel functions. Since this module is so small overall, the methods were not implemented in two different files.
	OSAL.cpp	The Operating System Abstraction Layer maps general functions to the operating system.
	WinSystem.cpp/h	The OSAL concept cannot be applied to all functions that are required. These functions were implemented in the code of this module.

## System Requirements

It is difficult to estimate the system requirements for targets based on different micro controllers and different development environments. The following is therefore giving a very rough scenario for the target system estimated resources.

Item	Requirement/Size	Comment
RAM	32k	Depends very much on the addressing structure of the controller and the used compiler and linker.
ROM (Flash)	100k	
Timing	1-2 ms Timer interrupt	2 ms is the minimum requirement, 1 ms would be much better.
	50 ms cyclic call from task level	This is needed to run the command interpreter.
I/O	UART and Hart MODEM Rx and Tx functions	Carrier detection would be helpful but is not required.
System	Simple math +-*/ memcpy() memset() memcmp()	Only a few standard library functions are required. There is no special need for multi tasking, messaging or semaphores.
	1 ms timing resolution	

**Table 1: Embedded System Requirements**



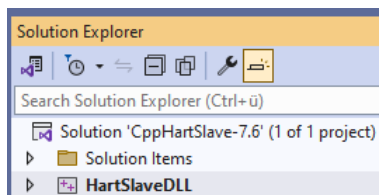
## Coding Conventions

Regarding this issue, I have only defined some formats that makes the scope of a label clearer. It's just to make the code easier to read. This simple type of coding convention can be used in both C++ and C#.

Snake Case			
local_variable	function_param_	m_member_var	mo_member_object
Variable with local scope	A function parameter has a trailing underscore	Basic type private member variable	Complex object member
s_member_var	so_member_object		
Basic type static private member variable	Complex static object member		
Pascal Case			
PublicVariable	PublicObject	AnyMethod	
Variable with public or internal scope	Object with public or internal scope	No difference between public and private	

## Visual Studio 2022

### Test Environment



There are only one project in this solution. The C++ Hart Slave is encapsulated in the HartSlaveDLL project. The solution is directly in the path on which you copied the package to.

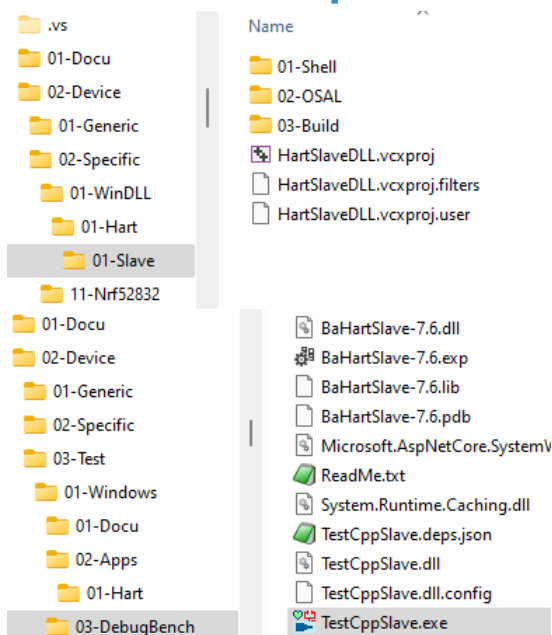
### Prerequisites

Microsoft Visual Studio Community 2022 (64-bit)  
Version 17.9.6  
© 2022 Microsoft Corporation.  
All rights reserved.

Microsoft .NET Framework  
Version 4.8.09032  
© 2022 Microsoft Corporation.  
All rights reserved.

The solution must be opened with VS 2022. However, the community version is sufficient. There are no further requirements.

### Development Directory Structure



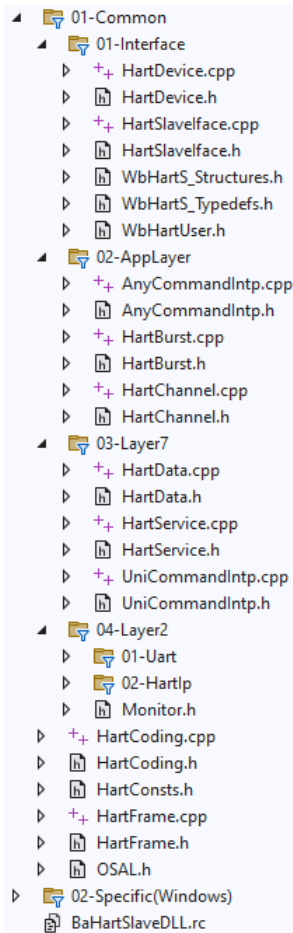
The project for the Hart Slave in C++ can be found in the directory:

.\02-Device\02-Specific\01-WinDLL\01-Hart\01-Slave.

However, most of the C++ sources used are located in the directory .\02-Device\01-Generic\ and its subdirectories.

The test software is only be found as executable in the path 03-DebugBench. The executable file TestCppSlave.exe and the simulation DLL BaHartSlave-7.6.dll are both located here. When you start debugging the executable ist started and loading the dll which is representing the slave device.

## Project Structure



The project structure is very similar to the directory structure. Here too there is a strict distinction between generic area and specific area.

The specific contents of the files are described in more detail in the list below.

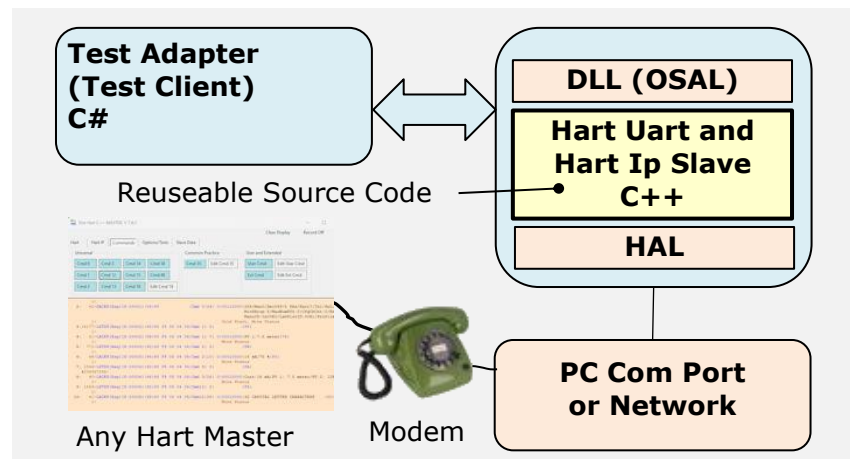
In contrast to the last published documentation, there is one significant difference. The data link layer is divided into the areas Uart and HartIp. The same applies to the Mac port in the OSAL directory.

## Getting Started

1. Unzip the file [hart-master-slave-c++-demo-7.6.1.zip](#) into a directory of your choice. For getting the required password please send an e-mail to: [harttools@borst-automation.de](mailto:harttools@borst-automation.de).
2. Open the solution `.\03-Slave\CppHartSlave-7.6.sln` with Visual Studio 2022. It has to be 2022. Other versions are not supported yet. Unless you have 2022 not installed on your computer. You can download it from microsoft: <https://visualstudio.microsoft.com/de/downloads/>.
3. The community version is sufficient enough and free of charge.
4. Perform a 'Build All'.
5. Start debugging and investigate the source code

# Test Interface

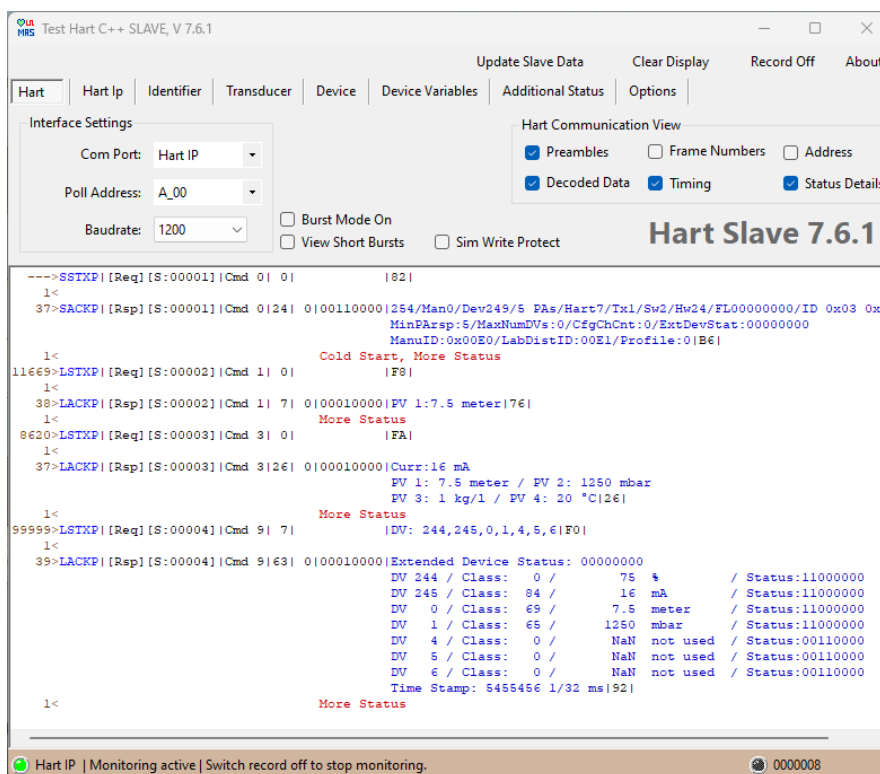
The Windows test adapter is a software developed in C#. This test adapter uses a Windows DLL in which the Hart Master is embedded. The DLL implements the HART Protocol, whose firmware was written in C++ for real time requirements.



**Figure 1: Architecture of the Test Environment**

The executable file for the test adapter is located at the following location:

.\03-Slave\03-Test\01-Windows\03-DebugBench\BaTestHartSlave.exe



**Screenshot 1: The Tab 'Hart'**

When the executable file is started, the container DLL for the slave is automatically loaded. The work surface is divided into two halves. Settings are made in the tab area, while the lower area is reserved for a monitor that shows the communication process. While the following tabs mostly deal with the slave data, the inputs in the interface have a fairly direct effect on the running software. For example, it is possible to activate burst mode without having to use the Hart command 109.

## Technical Data Sheet

### Data Exchange

Update Slave Data

Variables

Additional Status

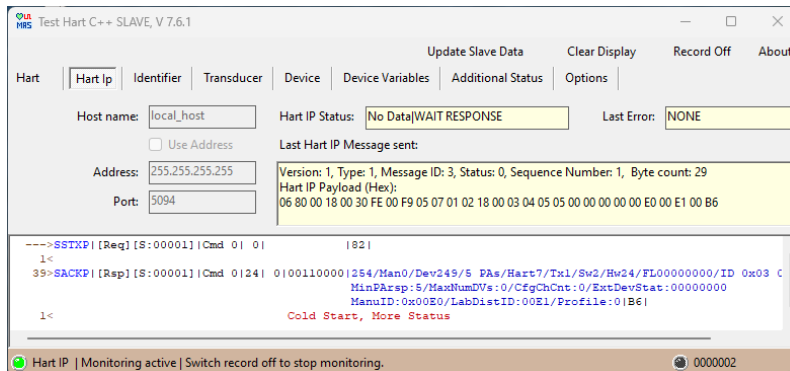
Options

Message: MESSAGE

Message: MOIN MOIN MOIN

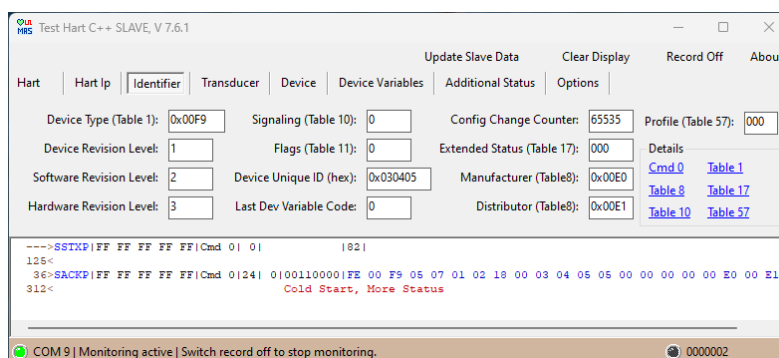
The following tabs deal with the transmitter data. If this data is edited, this is indicated by a yellow color. The menu button also turns yellow and must be clicked for the change to take effect in the slave.

If a parameter is changed by a master connected to the slave, this change appears in the display and the parameter in question is colored red



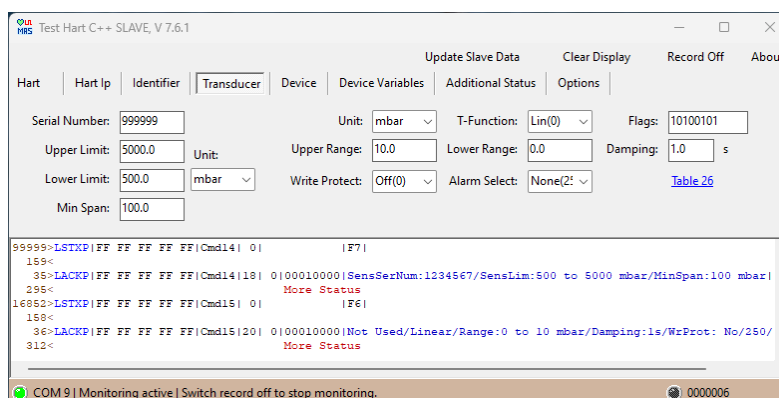
If Hart IP is used, additional parameters are needed to connect to the slave. However, currently the demo version works on localhost.

**Screenshot 2: The Tab 'Hart Ip'**



The tab 'Identifier' mainly deals with data related to command 0.

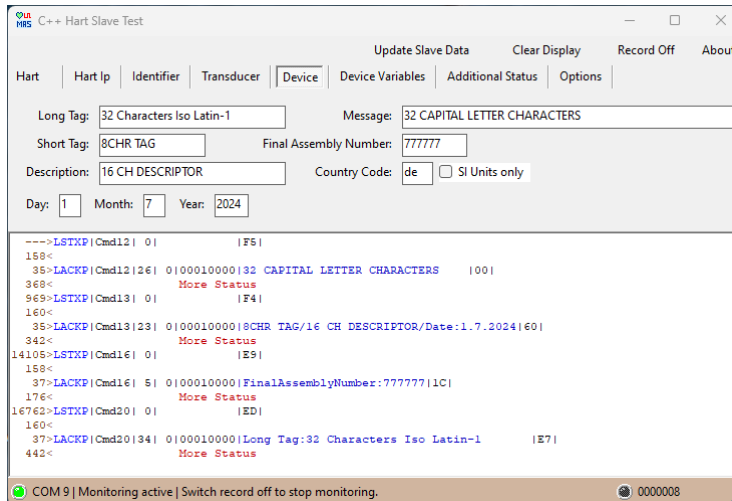
**Screenshot 3: The Tab 'Identifier'**



The tab 'Transducer' mainly deals with data related to the commands 14 and 15.

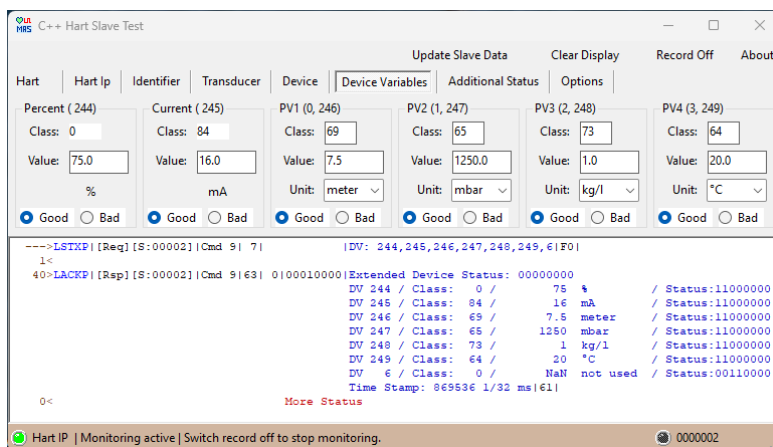
**Screenshot 4: The Tab 'Transducer'**

## Technical Data Sheet



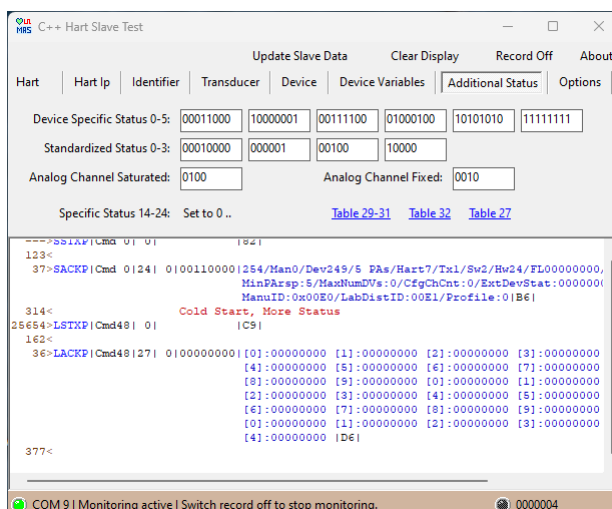
The tab 'Device' mainly deals with data related to the commands 12, 13, 16 and 20.

**Screenshot 5: The Tab 'Device'**



The 'Device Variables' tab provides access to the data needed to implement device variables. Currently, only device variable codes in the range 244-249 and 0..3 are accepted. These are the only required device variables. Of course, further variables for the user are possible at any time.

**Screenshot 6: The Tab 'Device Variables'**



This is about command 48. As already mentioned elsewhere, the slave manages the responses to the two masters separately and stores which response it has sent to a master. If something changes in the additional status, the software knows which master it affects because it can compare it with the copies.

**Screenshot 7: The Tab 'Additional Status'**

# Appendix

## Internet Links

<b>Specification Documents</b>	
<a href="#">HART Specifications</a>	FieldComm Group
<b>MODEMS</b>	
<a href="#">RS 232 Modem</a>	Microflex
<a href="#">USB Modem</a>	Endress + Hauser
<a href="#">Viator USB Modem</a>	Pepperl+Fuchs
<b>Ethernet-APL</b>	
<a href="#">Advanced Physical Layer</a>	FieldComm Group
<a href="#">Ethernet - To the Field</a>	Ethernet APL Organisation
<a href="#">HART-IP Developer Kit</a>	FieldComm Group

## Download Location

The software package described in this document can be downloaded via the following link:

<https://github.com/BorstAutomation/Hart-Master-Slave-8.0E.git>

## Legal Issues

### Conformity

This software package was developed to the best of my knowledge and my belief. The basis is the specifications of the Hart Communication Foundation in version 7.9.

However, it cannot be guaranteed that the software included in this package meets the HCF specifications in all required respects.

It is only possible to prove the conformity of this software after the user has integrated the software into his device and commissions HCF or a certified company to carry out this test. Under no circumstances am I, Walter Borst, responsible for carrying out such tests. Nor am I responsible for correcting any deficiencies resulting from such a test.

### Copyright

Copyright, Walter Borst, 2006-2024

Kapitaen-Alexander-Strasse 39, 27472 Cuxhaven, GERMANY

Fon: +49 (0)4721 6985100, Fax: +49 (0)4721 6985102

E-Mail: [info@borst-automation.de](mailto:info@borst-automation.de)

Home: <https://www.borst-automation.de/>

### No Warranty

Walter Borst expressly disclaims any warranty for the software package. This software package and related documents are provided "As Is".

By using this software package, the user agrees that no event shall Borst Automation or Walter Borst make responsible or liable for damages whatsoever. This includes, without limitation, damages for loss of business profits, loss due to business interruption, loss of business information, or any other pecuniary loss, arising out of the use of or the inability to use this software package.