neet1

	Header							Command	Data Length	Data
0	0	0	0	0	FF	0-FF	0-FF	0-FF	0-FF	

Notes	Action	Sub-Ad	dress	Command	Command (HEX)	Data Length	Data Byte:1	2	3	4	5	6	7 8	9	10	11
	NOOP	0		0	0	0										
	Reserve for core protocol	0		1	1	0						-				
Starts planned move	Start	0		2	2	0					_			_		
the production of the producti	Pause	0		3	3	0					_		_	_		
Stops planned move. Must be executed	r ause	- 0	_		J						-		_	_		
before controller will accept other commands.	Stop	0		4	4	0										
Toggles on/off state of debug LED	Debug LED	0		5	5	0										
- 55	Timing Master	0		6	6	0										
	Set Stored Name	0		7	7	1-10		String [1-10]	Characters, Null-terminated, Null p	naddedl						
	Set Device Address	0		8	8	1	2-255 [Byte]	Carigi 10	Transciore, real terminates, real p	Juducuj	_	т т	_	$\overline{}$		
	Set Common Line for Step Pulsing	0	$\overline{}$	9	9	1	0,1,2 [Byte]				-	-	_	_	_	
	Return Home All Motors	0		10	A	i i	0,1,2 [D)10j				-	-	_	_	_	
	Motors Max Step Rate	0		11	B	2	Ctr	eps/Second [Int]			_	-	_	_		
	MOLOIS MAX Step Nate	- 0		- 11	В		316	paraecorio (irit)								
	Alt Input Edge (RISING, FALLING, or CHANGE)	0		12	С	1	0,1,2 [Byte]				_	т т	_	_		
	Alt I/O Mode	0		13	D		Ring (0-255) [Byte]	Tip (0-255) [Byte]			+	-	_	_		
		0			- U	- 4		Пр (0-255) [Буке]			-	-	_	-		
	Set Joystick Watchdog			14	F	2	True/False (1,0) [Byte]				+	-	_	_		
	Alt Output Before Shot Delay Time	0		15				ime (ms) [int]				-	_			
	Alt Output After Shot Delay Time	0		16	10	2		ime (ms) [Int]								
L	Alt Output Before Shot Time	0		17	11	2		ime (ms) [Int]								
	Alt Output After Shot Time	0		18	12	2	Т	ime (ms) [Int]			_					
	Alt Output Trigger level	0		19	13	1	HIGH/LOW (1,0) [Byte]									
	Max Program Run Time	0		20	14	4		Max Run Time (mS) [Ulon	9]			1 T				
	Start Program Delay	0		21	15	4		Start Time Delay (seconds) [L	llong]							
	Set SMS / Continuous Program Mode	0		22	16	1	0 (SMS), 1 (Time Lapse Cont.) 2 (Video Cont.) [Byte]									
	Set Joystick Mode	0		23	17	1	True/False (1,0) [Byte]									
Causes the motors to go back and forth Between the start and stop positions	Set Ping-Pong Flag	0		24	18	1	True/False (1,0) [Byte]									
	Send all Motors to Program Start	0		25	19	0										
	Set Program Start point	0		26	1A	0										
	Set Program Start point	0			1A 1B	0										
True indicates 24 EPS false indicates 30	Set Program Start point Set Program Stop point	0		27	1B	0										
True indicates 24 FPS, false indicates 30 FPS	Set Program Start point						True/False (1,0) [Byte]									
	Set Program Start point Set Program Stop point Set Frames/Second Flag Status Request	0		27 28	1B 1C	0	<status type=""></status>		<returns> with header</returns>	and master ad	dress in f	front (00 00 0	0 00 00 FF	00 00 01	Length Data	
	Sed Program Start point Set Program Stop point Set Frames/Second Flag Status Request Firmware Version	0		27 28 100 100	1B 1C	0	<status type=""> Value Type [Int]</status>	Version i		and master ad	dress in f	front (00 00 0	0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Stop point Set Frames/Second Flag Status Request Firmware Version Run Status	0 0 0		27 28 100 100 101	1B 1C 64 65	0 0	<status type=""> Value Type [Int] Value Type [Byte]</status>	Version i 0 = Stopped, 1 = Paused, 2 = Running	# 	and master ad	dress in f	front (00 00 0	0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Stop point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time	0 0 0 0 0		27 28 100 100 101 101	1B 1C 64 65 66	0 0 0 0 0	<status type=""> Value Type [Int] Value Type [Byte] Value Type [Ulong]</status>	0 = Stopped, 1 = Paused, 2 = Running		and master ad	dress in f	front (00 00 0	0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Stop point Set Frames/Second Flag Status Request Firmwer Version Run Status Run Time Currently Exposing	0 0 0 0 0		27 28 100 100 101 102 103	1B 1C 64 65 66 67	0 0 0	 <status type=""> Value Type [Int] Value Type [Byte] Value Type [Ulong] Value Type [Byte]</status>	0 = Stopped, 1 = Paused, 2 = Running True/False	# 	and master ad	dress in f	front (00 00 0	0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Finemer Vestor Finemer Vestor Run Time Currently Exposing Timing Master Value	0 0 0 0 0 0		27 28 100 100 101 101 102 103 104	1B 1C 64 65 66 67 68	0 0 0 0 0 0	<status type=""> Value Type [Int] Value Type [Byte] Value Type [Ulong] Value Type [Byte] Value Type [Byte]</status>	0 = Stopped, 1 = Paused, 2 = Running	Time (ms)				0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Storp point Set Frames/Second Flag Status Request Firmwer Version Run Status Run Time Currently Exposing Timing Master Value Name	0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105	1B 1C 64 65 66 67 68 69	0 0 0 0 0 0 0	<status type=""> Value Type [Int] Value Type [Byte] Value Type [Byte] Value Type [Byte] Value Type [Byte] Value Type [String]</status>	0 = Stopped, 1 = Paused, 2 = Running True/False True/False	Time (ms) String [1-10 Characters				0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Frameser Version Run Status Run Status Quirently Exposing Timing Master Value Name Motors Max Step Rate	0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106	1B 1C 64 65 66 67 68 69 6A	0 0 0 0 0 0 0 0	<status type=""> Value Type [Int] Value Type [Byte] Value Type [Int]</status>	0 = Stopped, 1 = Paused, 2 = Running True/False True/False Steps/Seco	Time (ms) String [1-10 Characters	, Null-terminate			0 00 00 FF	F 00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Mostley Value Motors Max Step Rate Voltage Reading	0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107	1B 1C 64 65 66 67 68 69 6A 6B	0 0 0 0 0 0 0 0	<status type=""> Value Type [Int] Value Type [Byte] Value Type [Siring] Value Type [Vint] Value Type [Fired]</status>	0 = Stopped, 1 = Paused, 2 = Running True/False True/False Steps/Sect Voltage (V) (Fixed poin	Time (ms) String [1-10 Characters and t - must divide by 100 on master s	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Stop point Set Frames/Second Flag Status Request Firmware Version Run Status Run Status Run Tirene Trene Program Status Name Motors Mass Step Rate Voltage Reading Current to Motors Current to Motors	0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108	1B 1C 64 65 66 67 68 69 6A 6B 6C	0 0 0 0 0 0 0 0 0	<status [fixed]="" [fixed]<="" [int]="" [iyte]="" [string]="" [syte]="" td="" type="" value=""><td>0 = Stopped, 1 = Paused, 2 = Running True/False True/False Steps/Seco Voltage (V) (Fixed poin Current (amps) (Fixed p</td><td>Time (ms) String [1-10 Characters</td><td>, Null-terminate</td><td></td><td></td><td>0 00 00 FF</td><td>00 00 01</td><td>Length Data</td><td></td></status>	0 = Stopped, 1 = Paused, 2 = Running True/False True/False Steps/Seco Voltage (V) (Fixed poin Current (amps) (Fixed p	Time (ms) String [1-10 Characters	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Quirrenty Exposing Timing Master Value Local Control Contr	0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D	0 0 0 0 0 0 0 0 0	Status Type Value Type [Int] Value Type [Int] Value Type [Iden] Value Type [Iden] Value Type [Syte] Value Type [Siring] Value Type [Int] Value Type [Fixed] Value Type [Fixed] Value Type [Syte] Value Type [Tixed] Value Type [Tixed]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Steps/Sec Voltage (V) (Fosed por Current (amps) (Fused por 0,1,2	Time (ms) String {1-10 Characters and II – must divide by 100 on master int – must divide by 100 on master	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Gurrenty Expositus Inning Name Motors Mass Step Rate Voltage Reading Current to Motors At Input Edge (RISING, FALLING, or CHANGE) All Input Edge (RISING, FALLING, or CHANGE)	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D	0 0 0 0 0 0 0 0 0 0 0	<status [in<="" [int]="" [inted]="" td="" type="" value=""><td>0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Stepe/Sec Votage (V) (Fued poin Current (anglo) (Fued poin 0,1,2 [Byte 0] Ring (0-255)</td><td>Time (ms) String [1-10 Characters and It - must divide by 100 on master int must divide by 100 on master [Byte 1] Tip (0-255)</td><td>, Null-terminate</td><td></td><td></td><td>0 00 00 FF</td><td>00 00 01</td><td>Length Data</td><td></td></status>	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Stepe/Sec Votage (V) (Fued poin Current (anglo) (Fued poin 0,1,2 [Byte 0] Ring (0-255)	Time (ms) String [1-10 Characters and It - must divide by 100 on master int must divide by 100 on master [Byte 1] Tip (0-255)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Master Value Name Motors Mas Step Rate Voltage Refers Authority (Signal Control of the Status Control of the Statu	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D 6E	0 0 0 0 0 0 0 0 0 0 0 0	<status [int]="" [int]<="" [inted]="" td="" type="" types="" value=""><td>0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Steps/Sect Voltage (V) (Fixed poir Current (amps) (Fixed poir 0,1,2 (Byte 0) Ring (0,255) (Byte 0) Ring, Hight Low (1,0)</td><td>Time (ms) String [1-10 Characters and temperature of the must divide by 100 on master aint – must divide by 100 on master [Byte 1] Tip (0-255) [Byte 1] Tip (HghtLow(1.0)</td><td>, Null-terminate</td><td></td><td></td><td>0 00 00 FF</td><td>00 00 01</td><td>Length Data</td><td></td></status>	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Steps/Sect Voltage (V) (Fixed poir Current (amps) (Fixed poir 0,1,2 (Byte 0) Ring (0,255) (Byte 0) Ring, Hight Low (1,0)	Time (ms) String [1-10 Characters and temperature of the must divide by 100 on master aint – must divide by 100 on master [Byte 1] Tip (0-255) [Byte 1] Tip (HghtLow(1.0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Misslet Value Motors Mars Step Rate Voltage Reading Current to Modors Alt Input Edge (RISING, FALLING, or CHANGE) Alt Input Edge (RISING, FALLING, or CHANGE) Limit Switch Hight Low Status Alt Upda Before Shot Delay Time Alt Old Modes	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D 6E 6F 70	0 0 0 0 0 0 0 0 0 0 0	<status [int]="" [inted]="" td="" type="" valu<="" value=""><td>0 = Stopped, 1 = Paused, 2 = Running Trus-Fidee Trus-Fidee Steps/Sec Voltage (V) (Fixed por Current (amps) (Fixed por Gunernt (amps) (Fixed por Byte 0) Ring (0:255) [Byte 0] Ring, HighLow (1,0)</td><td>Time (ms) Siring [1-10 Characters and 1- must divide by 100 on master int- must divide by 100 on master [Byte 1] Tip (0-255) [Byte 1] Tip (1-255)</td><td>, Null-terminate</td><td></td><td></td><td>0 00 00 FF</td><td>00 00 01</td><td>Length Data</td><td></td></status>	0 = Stopped, 1 = Paused, 2 = Running Trus-Fidee Trus-Fidee Steps/Sec Voltage (V) (Fixed por Current (amps) (Fixed por Gunernt (amps) (Fixed por Byte 0) Ring (0:255) [Byte 0] Ring, HighLow (1,0)	Time (ms) Siring [1-10 Characters and 1- must divide by 100 on master int- must divide by 100 on master [Byte 1] Tip (0-255) [Byte 1] Tip (1-255)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Status Run Time Currently Exposing Timing Master Value Name Motors Max Step Rate Votage Reading Current to McCore At Input Edge (No Mode) At Input Edge (No Mode) Limits March Highly Low Status Alt Output Before Shot Delay Time Alt Output Before Shot Delay Time Alt Output After Shot Delay Time Alt Output After Shot Delay Time Alt Output After Shot Delay Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111 111 112	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D 6E 6F 70 71	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Value Type [25] Value Type [25] Value Type [35] Value Type [35] Value Type [35] Value Type [35] Value Type [47]	0 = Stopped, 1 = Paused, 2 = Running TrusFalse TrusFalse Stepa/Sec Votage (V) (Fixed point Current (amps) Fixed point (Byte 0) Ring (0-25) (Byte 0) Ring, High-Low (1.0) True (im)	Time (ms) String [1-10 Characters and the must divide by 100 on master sint – must divide by 100 on master sint – must divide by 100 on master [Byte 1] Tip (0:255) [Byte 1] Tip (HighT.cov(1,0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Mester Vidue Motors Man Step Rate Vidue All Input Edge (RSING, FALLING, or CHANGE) All Uput Affer Shd Delay Time All Output Affer Shd Delay Time All Output Before Shd Time All Output Before Shd Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111 112 113 114	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D 6E 6F 70 71	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Value Type (rd) Value Type (rd) Value Type (rd) Value Type (Byte) Value Type (Freed)	0 = Stopped, 1 = Passed, 2 = Running TrueFalse TrueFalse Steps/Sec Votage (V) (Fined por Current (amps) (Fixed por 0.1.2 [Byte 0] Ring (0.255) [Byte 0] Ring, HighLow (1) Trine (im Trine (im	Time (ms) String [1-10 Character and I = must divide by 100 on master int = must divide by 100 on master [Byte 1] Tip. (i-255) [Byte 1] Tip. Hagh Low(1,0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Burl Time Currently Exposing Timing Master Value Name Motors Max Step Rate Voltage Reading Current to Motors At Input Edge (RISING) FALLING, or CHANGE) At Input Edge (RISING) FALLING, or CHANGE) Liming Switch Hight Low Status Liming Switch Hight Low Status All Output Before Shot Time All Output After Shot Delay Time All Output After Shot Starts All Output After Shot Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 111 112 113 114 115	1B 1C 64 65 66 67 68 68 6C 6D 6E 6F 70 71 72 73	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	-Status Type Vake Type [Byte] Vake Type [Face] Vake Type [Byte]	0 = Stopped, 1 = Paused, 2 = Running TrusFalse TrusFalse Steps/Sec Vottage (V) (Fixed poil Current (arms) (Fixed poil (Byte 0) Reng (0-255) (Byte 0) Reng (0-255) (Byte 0) Reng (10) True (im True (im True (im True (im)	Time (ms) String [1-10 Character and I = must divide by 100 on master int = must divide by 100 on master [Byte 1] Tip. (i-255) [Byte 1] Tip. Hagh Low(1,0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Mester Vidue Motors Man Step Rate Vidue All Input Edge (RSING, FALLING, or CHANGE) All Uput Affer Shd Delay Time All Output Affer Shd Delay Time All Output Before Shd Time All Output Before Shd Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111 112 113 114	1B 1C 64 65 66 67 68 69 6A 6B 6C 6D 6E 6F 70 71	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Value Type [ref] Value Type [ref] Value Type [ref] Value Type [Worq] Value Type [Worq] Value Type [Syle] Value Type [Syle] Value Type [Fixed] Value Type [Value Type [V	0 = Stopped, 1 = Paused, 2 = Running TrusFalse TrusFalse Stepa/Sec Votage (V) (Fixed point Current (amps) Fixed point (Byte 0) Ring (0-25) (Byte 0) Ring, High-Low (1.0) True (im)	Time (ms) String [1-10 Character and I = must divide by 100 on master int = must divide by 100 on master [Byte 1] Tip. (i-255) [Byte 1] Tip. Hagh Low(1,0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Burl Time Currently Exposing Timing Master Value Name Motors Max Step Rate Voltage Reading Current to Motors At Input Edge (RISING) FALLING, or CHANGE) At Input Edge (RISING) FALLING, or CHANGE) Liming Switch Hight Low Status Liming Switch Hight Low Status All Output Before Shot Time All Output After Shot Delay Time All Output After Shot Starts All Output After Shot Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 111 112 113 114 115	1B 1C 64 65 66 67 68 68 6C 6D 6E 6F 70 71 72 73	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Value Type [ref] Value Type [ref] Value Type [ref] Value Type [Worq] Value Type [Worq] Value Type [Syle] Value Type [Syle] Value Type [Fixed] Value Type [Value Type [V	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Steps/Sec Votage (V) (Fined por Current (amps) (Fixed por 0,1.2 [Byte 0] Ring (0.255) [Byte 0] Ring, Highlow (1) Time (m) Time (m) HIGHLOW (1,0)	Time (ms) String [1-10 Character and I = must divide by 100 on master int = must divide by 100 on master [Byte 1] Tip. (i-255) [Byte 1] Tip. Hagh Low(1,0)	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Master Value Motors Motors Voltage Reading Current to Motors Current to Motors All Input Edge (RISNO, FALLING, or CHANGE) All Input Edge (RISNO, FALLING, or CHANGE) All Lough Before Shot Delay Time All Coulput Before Shot Delay Time All Coulput After Shot Time All Output After Shot Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 112 113 114 115 116	64 65 65 67 67 68 69 69 60 60 60 60 60 60 60 60 70 71 72 73 74	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Vake Type [rd] Vake Type [rd] Vake Type [rd] Vake Type [ld]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse Steps/Sec Votage (V) (Fined por Current (amps) (Fixed por 0,1.2 [Byte 0] Ring (0.255) [Byte 0] Ring, Highlow (1) Time (m) Time (m) HIGHLOW (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Vereich Run Status Run Time Currently Exposing Timing Master Value Name Motors Max Steps Date Motors Max Steps Date At Input Edge (RISNG, FALLING, or CHANGE) All tiput Edge (RISNG, FALLING, or CHANGE) All tiput Edge (RISNG, FALLING, or CHANGE) All toput Before Shot Delay Time At Output Before Shot Delay Time At Output Before Shot Delay Time At Output Before Shot Delay Time At Output Before Shot Delay Time At Output Before Shot Time At Output Before Shot Control At Output Before Shot Delay Time At Output Before Shot Delay Time At Output Stories Start Program Delay Start Program Delay Start Program Delay Start Program Mode	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 100 101 102 103 104 105 106 107 109 110 111 112 113 114 115 116 117 118	64 65 65 67 67 68 69 68 60 60 60 60 60 60 60 71 71 72 73 73 75 76	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Value Type [ref] Value Type [ref] Value Type [ref] Value Type [Ulorq] Value Type [Ulorq] Value Type [Stre] Value Type [Stre] Value Type [Ulorq] Value Type [Ulorq] Value Type [Flexel] Value Type [ref] Value Type [ref] Value Type [ref] Value Type [Ver] Value Type [Ulorq] Value Type [Vlorq] Value Type [Vlorq] Value Type [Vlorq]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse TrueFalse Voltage (V) (Fand por Current (amps) (Fand por 0,12 [Byte 0] Ring (0.255) [Byte 0] Ring, Hight.ow (1.0) Trine (int Fine (int) HIGHLOW (1.0) Start 0 (SMS), 1 (Cont.), 2 (Vid. Cont)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Frames/Second Flag Status Request Frames/Second Flag Status Request Frames/Second Flag Ron Status Ron	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 112 113 114 115 116 117 117 118	1B 1C 64 65 66 67 68 68 68 69 6A 68 69 70 71 72 73 74 75 76 77	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Vake Type [Iri]	0 = Stopped, 1 = Paused, 2 = Running TrusFalse TrusFalse Steps/Sec Votage (V) (Fixed pot Current (amps) (Fixed pot 0, 1,2 [Byte 0] Ring, (0,255) [Byte 0] Ring, (1,0) Trine (im Trine (im HIGH-LOW (1,0) Trine (im HIGH-LOW (1,0) Start 0 (SMS), 1 (Cont.), 2 (Vid. Cont.) TrusFalse (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Master Value Name Motors Max Step Rate Votage Reading Votage Reading At Input Step (ISSNC FALLING, or CHANGE) All 100 Mode Limits Work Flag May 100 Mode Limits Work Flag May 100 Mode Limits Work Flag May 100 Mode All Output Before Shot Delay Time All Output Before Shot Delay Time All Output After Shot Delay Time All Output Refore Shot Time All Output After Shot Delay Time All	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 112 113 114 115 116 117 117 118	1B 1C 64 65 66 66 67 68 68 68 60 60 60 60 60 60 60 60 60 60 60 60 60	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Value Type [ref] Value Type [ref] Value Type [ref] Value Type [lufora] Value Type [red] Value Type [red] Value Type [red] Value Type [red] Value Type [lufora]	0 = Stopped, 1 = Passed, 2 = Running TrueFalse TrueFalse TrueFalse Votage (V) (Fand por Current (amps) (Fand por 0,12 [Byte 0] Ring, HighTow (1,0) True (im Fine (im HIGHLOW (1,0) Start 0 (SMS), 1 (Cont.), 2 (Vot. Cont.) TrueFalse (1,0) TrueFalse (1,0) TrueFalse (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Quirretify Exposing Timing Mester Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue Motors Man Step Rate Vidue All Input Edge (RSING, FALLING, or CHANGE) All Input Edge (RSING, FALLING, or CHANGE) All Uput After Shot Deiey Time All Output After Shot Time All Output After Shot Time All Output Before Shot Time All Output Before Shot Time All Output Before Shot Time All Output After Shot Time All Output Before Shot Time All Output Before Shot Time All Output After Shot Time All Output Before Shot Time All Output After Shot Time All Output Before Shot Time All Output After Shot Time	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 111 112 113 114 115 116 117 118 119 119 119 119 119 119 119 119 119	18 1C 64 65 66 66 68 68 66 66 66 66 67 70 71 72 73 74 76 79 79	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Vaxer Type [ref] Value Type [ref] Value Type [ref] Value Type [lef] Value Type [ref] Value Type [ref] Value Type [ref] Value Type [ref] Value Type [lef]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse TrueFalse Votage (V) (Sepad por Current (amps) (Fleed por Current (amps) (Fleed por 0,1,2 [Byte 0] Ring (0,255) [Byte 0] Ring, Hightow (1,0) The (im Time (im Time (im HIGHLOW (1,0) Sepad (1,0) TrueFalse (1,0) TrueFalse (1,0) TrueFalse (1,0) TrueFalse (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
FPS Reports the percentage complets of the	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Vereich Run Status Run Time Currently Exposing Timing Master Value Name Motors Max Steps atte Motors Max Steps atte Motors Max Steps atte Current to Motors Current to Motors Alt Input Edge (RISNG, FALLING, or CHANGE) Alt 100 Mode Limits Worth High Low Status Alt Output Before Shot Delay Time Alt Output Before Shot Delay Time Alt Output Before Shot Time Alt Output Before Shot Status Start Program Delay Start Program Delay Start Program Delay Start Program Mode Controller Power Cycle Joystick Mode Ping-Prog Flag Joystick Mode Joystick Mode Ned Status Joystick Mode Joystick Mode	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 104 105 106 107 108 109 110 111 112 113 114 115 116 117 117 118	18 1C 64 65 65 66 67 68 68 66 6C 6D 6E 77 73 74 75 76 77 77 77 77 77 77 77 77 77 77 77 77	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Value Type (rd) Value Type (rd) Value Type (rd) Value Type (ld)	0 = Stopped, 1 = Passed, 2 = Running TrueFalse TrueFalse TrueFalse Votage (V) (Fand por Current (amps) (Fand por 0,12 [Byte 0] Ring, HighTow (1,0) True (im Fine (im HIGHLOW (1,0) Start 0 (SMS), 1 (Cont.), 2 (Vot. Cont.) TrueFalse (1,0) TrueFalse (1,0) TrueFalse (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	00 00 01	Length Data	
Reports the percentage complete of the current program as a whole number. The three least sopnicant bits of the byte of the molers. Montor 1 = bit 0, motor 2 = bit 1.	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Mester Value Motors Max Step Rate Voltage Reading Current to Motors Voltage Reading Current to Motors All Input Edge (RISNIS FALLING, or CHANGE) All Input Edge (RISNIS FALLING, or CHANGE) All Input Edge (RISNIS FALLING, or CHANGE) All Output After Shot Delay Time All Output After Shot Time All Output After Shot Time All Output Refore Shot Delay Time All Output Refore Shot Delay Time All Output Refore Shot Gelley Time All	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111 112 113 114 115 116 117 118 119 120 120	18 1C 64 65 66 66 68 68 66 66 66 66 67 70 71 72 73 74 75 76 79	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Types Vaxer Type [ref] Value Type [ref] Value Type [ref] Value Type [lef] Value Type [ref] Value Type [ref] Value Type [ref] Value Type [ref] Value Type [lef]	0 = Stopped, 1 = Passed, 2 = Running TrusFalse TrusFalse TrusFalse TrusFalse Votage (V) (Fand por Current (amps) (Fand por 0,12 [Byte 0] Ring (0,255) [Byte 0] Ring, Hightow (1,0) Trine Im Fire Im HIGHLOW (1,0) Start 0 (SMS), 1 (Cont.), 2 (Vot. Cont.) TrusFalse (1,0) TrusFalse (1,0) TrusFalse (1,0) TrusFalse (1,0) TrusFalse (1,0) TrusFalse (1,0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 0 00 00 FF	6 00 00 01	Length Data	
Reports the percentage complete of the current program as a whole number. The three least significant bits of the byte represent the modern affabric states for each of the motors. Motor 1 = bit 0, motor 2 = bit 1, motor 3 = bit 2, motor 3 = bit 1, motor 3 = bit 2, motor 3 = bit 3, motor 3 = bit 1, motor 3 = bit 3, motor 3 = bit	Set Program Start point Set Program Start point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Mester Value Motors Max Step Rate Voltage Reading Current to Motors Voltage Reading Current to Motors All Input Edge (RISNIS FALLING, or CHANGE) All Input Edge (RISNIS FALLING, or CHANGE) All Input Edge (RISNIS FALLING, or CHANGE) All Output After Shot Delay Time All Output After Shot Time All Output After Shot Time All Output Refore Shot Delay Time All Output Refore Shot Delay Time All Output Refore Shot Gelley Time All	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 102 103 104 105 106 107 109 110 111 111 113 114 115 116 117 118 119 119 119 119 119 119 119 119 119	18 1C 65 66 68 68 69 68 66 6C 6C 6C 77 71 72 72 73 74 75 76 77 77 77 78 78 78 78 78	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Vake Type [Int]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse TrueFalse TrueFalse Votage (V) (Fine Good Current (amps) (Fixed pro) 0.1.2 [Byte O] Ring (0.255) [Byte O] Ring, Highlow (1.0) True firm HIGHLOW (1.0) True firm HIGHLOW (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0)	Time (ms) String [1-10 Characters and characters are characters and characters are characters a	, Null-terminate			0 00 00 FF	000000	Length Data	
Reports the percentage complete of the current program as a whole number. The three least significant bits of the byte represent the motor attach states for each of the motor. More 1 = bit 0, motor 2 = bit Percentage 1 = bit 1, motor 2 = bit Percentage 1 = bit 1, motor 2 = bit Percentage 1 = bit 1, motor 2 = bit Percentage 1 = bit 1, motor 2 = bit Percentage 1 = bit 1, motor 2	Set Program Slart point Set Program Slart point Set Frames/Second Flag Status Request Firmware Version Run Status Run Time Currently Exposing Timing Master Value Name Motors Max Slaye Slate Motors Max Slaye Slate All Input Slage (RISNG, FALLING, or CHANGE) All 100 Mode Limits Wilder Shat Delay Time Alt Output Before Shot Delay Time Alt Output	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 102 103 104 105 106 107 108 109 110 111 111 112 113 114 115 116 117 118 119 120 121 122 123	18 1C 64 65 65 66 67 68 69 68 66 6C 6D 77 73 74 75 76 77 78 78 79 77 7	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	-Slatus Type -Value Type (Byte)	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse TrueFalse TrueFalse Voltage (V) (Feed poir Current (amps) (Feed poir 0,12 [Byte 0] Ring (0.255) [Byte 0] Ring, Hight.ow (1.0) True fire Irine (int Irine (int) HIGHLOW (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) 0-100 0-7	Time (ms) Siring (1-10 Characters and 1-must divide by 100 on master or must be 100 on must be 100 on master or must be 100 on master or must be 100 on must be 100 on master or must be 100 on master	, Null-terminate			0 00 00 FF	6000000	Length Deta	
Reports the percentage complete of the current program as a whole number. The three least significant bits of the byte represent the modern affabric states for each of the motors. Motor 1 = bit 0, motor 2 = bit 1, motor 3 = bit 2, motor 3 = bit 1, motor 3 = bit 2, motor 3 = bit 3, motor 3 = bit 1, motor 3 = bit 3, motor 3 = bit	Set Program Start point Set Program Start point Set Program Stort point Set Frames/Second Flag Status Request Firmwere Vereiton Run Status Run Time Currently Exposing Timing Master Value Name Motors Mas Step Rate Current to Metors Current to Metors Alt Input Edge (RISING: FALLING, or CHANGE) Alt Input Edge (RISING: FALLING, or CHANGE) Alt Output Before Shot Delay Time Alt Output Before Shot Delay Time Alt Output Before Shot Time Alt Output After Shot Delay Time Alt Output Before Shot Delay Time Alt Delay T	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0		27 28 100 100 101 101 102 103 103 104 105 106 107 108 109 110 111 111 115 116 117 117 118 119 120 121 122 122 123	18 1C 64 66 66 67 68 69 69 6A 68 6C 6C 6C 77 71 72 72 73 74 75 76 77 78 77 77 77 77 77 77 77 77 77 77 77	0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0	Status Type Vake Type [Int]	0 = Stopped, 1 = Paused, 2 = Running TrueFalse TrueFalse TrueFalse TrueFalse Votage (V) (Fine Good Current (amps) (Fixed pro) 0.1.2 [Byte O] Ring (0.255) [Byte O] Ring, Highlow (1.0) True firm HIGHLOW (1.0) True firm HIGHLOW (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0) TrueFalse (1.0)	Time (ms) Siring (1-10 Characters and 1-must divide by 100 on master or must be 100 on must be 100 on master or must be 100 on master or must be 100 on must be 100 on master or must be 100 on master	, Null-terminate			0 00 00 FF	00 00 00 01	Length Data	

Motors		NOOP Reserve for core protocol	1-3 1-3	0	0	0				+	
	Cuts power to motor when not executing a									+	
	move. True by default.	Motor Sleep	1-3	2	2	1	True/False (1,0) [Byte]				
	Must enabled before executing a move.	Motor Enable	1-3	3	3	1	True/False (1,0) [Byte]				
	Stops motor, even if a planned move is in	Stop Motor Now	1-3	4	4	0					
	progress.	CIOD HICKO TON		-	-	, i				+	
	Number of steps the motor should move in addition to the commanded distance when reversing direction.	Set Backlash Steps	1-3	5	5	2	:	Steps [Uint]			
General Motor Commands	Number of microsteps per full motor step. There are 200 full steps per rotation of the motor (and ~3800 full steps per gearbox output shaft rotation)	Set Microstep Value	1-3	6	6	1	1, 2, 4, 8, 16 [Byte]				
	output shart rotation)	Set Motor Max Step Speed	1-3	7	7	2	Sten	s/Second [Uint]		+	
	Flips motor direction, regardless of current program	Set Direction	1-3	8	8	1	0, 1 [Byte]				
	Saves home limit position	Set Home Limit Here	1-3	9	9	0					
	Saves end limit position	Set End Limit Here	1-3	10	A	0					
		Send Motor to Home Limit	1-3	11	В	0				+	
		Send Motor to End Limit	1-3	12	С	0					
	Does not apply to finite manual moves	Set Continuous Speed	1-3	13	D	4		Steps/Second [float]			
Manual Move	Does not apply to finite manual moves	Set Motor Continuous Motion Accel/Decel Rate	1-3	14	E	4		Steps/Second^2 [float]			
Commands	Direct move command, does not require use of "start" and "stop" commands.	Execute Simple Motor Move	1-3	15	F	5	Dir (0, 1) [Byte]		Steps [Ulong]		
		Set Program Start point	1-3	16	10	4		Step position [long]			
	1 = Linear, 2 = Quadratic, 3 = Inverted	Set Program Stop point	1-3	17	11	4		Step position [long]			
	Quadratic	Set Easing (Ramping) Mode	1-3	18	12	1	1, 2, 3			+	
Programmed Travel	How many shots should this motor wait before moving?	Set Lead-In Shots / Time	1-3	19	13	2	Shots (SMS or time lapse	cont.) / Time ms (Video cont.) [Uint]			
Commands		Set Travel Shots(SMS) / Travel Time (Cont.)	1-3	20	14	4		Shots (SMS) or Total Travel Time (ms)		4	
		Set Program Accel Set Program Decel	1-3 1-3	21	15 16	4		Accel Period – Shots (SMS) or Time in m Decel Period – Shots (SMS) or Time in m	s (Cont.) [Ulong)]		
		Send Motor to Program Start Point	1-3	23	17	0		December of Short (SMS) or Time in the	is (Coni.) [biologj		
		Send Motor to Program Stop Point	1-3	24	18	0				$\overline{}$	
				•			•		'		
Stop-Motion Travel	Manual SMS movement. Not yet implemented.	Advance One SMS Increment	1-3	25	19	0					
Commands	Manual SMS movement. Not yet implemented.	Go Back One SMS Increment	1-3	26	1A	0					1 1 1 1 1
	Sets the current position as home, disables limits, and sets start/stop positions to home position.	Reset Limits and Program Start/Stop Positions	1-3	27	1B	0					
	The controller will automatically select the highest resolution microstepping (up to 14 stepping) that can be used to achieve the rooyam parameters. It will also report back the settling it uses. 0 will be reported when the command is called at an illegal time (i.e. when the motor is in motion), 255 will be reported when the specif required by the current plan parameters exceeds the controller's top speed.	Auto Set Program Microsteps	1-3	28	1C	0	Value Type [Uint]	0, 4, 8, 16, 255			
		Set Start Here	1-3	29	1D	0					
		Set Stop Here	1-3	30	1E	0					
		Status Request	1-3	100			<status type=""></status>		<returns> with header and master add</returns>	danna in frank (00 00 00 00 00 00 55 t	20 00 04 Length Date)
	 	Motor Enable	1-3	100	64	0	Value Type [Byte]	True/False (1,0)	veturns/ with neader and master add	1 655 11 1/OIL (00 00 00 00 00 FF 0	5 00 01 Length Data)
		Backlash Steps	1-3	101	65	0	Value Type [Uint]	Steps			
		Microstep Value	1-3	102	66	0	Value Type [Byte]	1, 2, 4, 8, 16			
General Motor Query		Direction	1-3	103	67	0	Value Type [Byte]	0, 1			
Commands		Motor Max Step Speed	1-3	104	68	0	Value Type [Int]	Steps/Sec	ond		
	<u> </u>	End Limit Position Current Motor Position	1-3 1-3	105 106	69 6A	0	Value Type [Long] Value Type [Long]		Position Position		
	<u> </u>	Current Motor Position Motor Running	1-3	106	6B	0	Value Type [Long] Value Type [Byte]	True/False (1,0)	r-using r		
		motor running						11001000 (1,0)			
Manual Move		Continuous Speed	1-3	108	6C	0	Value Type [Psudo-float–Fixed point – must divide by 100 on master side]		Steps/Second		
Query Commands		Motor Continuous Motion Accel/Decel Rate	1-3	109	6D	0	Value Type [Psudo-floatFixed point – must divide by 100 on master side]		Steps/Second^2		
		Easing (Ramping) Mode	1-3	110	6E	0	Value Type [Byte]	1, 2, 3			
	<u> </u>	Program Start point	1-3 1-3	111 112	6F 70	0	Value Type [Long] Value Type [Long]		Position Position		
Programmed	<u> </u>	Program Stop point Travel Shots(SMS) / Travel Time (Cont.)	1-3	112	70	0	Value Type [Long] Value Type [Ulong]	Shote (SMS) o	r Total Travel Time (ms) (cont.)		
Travel Query		Lead-In Shots / Time (Cont.)	1-3	114	72	0	Value Type [Int]	Shots (SMS or time lance cont.)	/ Time ms (Video cont.)	- 	
Commands		Program Accel	1-3	115	73	0	Value Type [Ulong]	Accel Period – S	/ Time ms (Video cont.) hots (SMS) or Time in ms (Cont.)		
		Program Decel	1-3	116	74	0	Value Type [Ulong]	Decel Period – S	hots (SMS) or Time in ms (Cont.)		
		Check Motor Sleep State	1-3	117	75	1	Value Type [Byte]	True/False (1,0)			
	•										

													_			_
	NOOP	4	0	0	0											_
	Reserve for core protocol	4	1	1	0											
	Camera Enable	4	2	2	1	True/False (1,0) [Byte]										
Triggers exposure with length set by "Exposure Time" command.	Expose Now	4	3	3	0											
	Trigger Time	4	4	4	4		Exposure Time (mS) [Ulor	ngl								
	Focus Time	4	5	5	2	Focus	Time (mS) [Uint]	ſ								1
The system will stop a move once it reaches the max number of camera exposures.	Max Shots	4	6	6	2		Count [Uint]									
	Exposure Delay	4	7	7	2	De	lay (mS) [Uint]									ï
	Focus w Shutter	4	8	8	1	True/False (1,0) [Byte]										
This causes two trigger signals to be ser the camera in the event that the user has the camera in "mirror up" mode.	nt to Mirror Up (Repeat Shot)	4	9	9	1	True/False (1,0) [Byte]										•
Length of SMS interval	Interval	4	10	A	4		Interval Time (mS) [Ulong	3]								
	Camera Test Mode	4	11	В	1	True/False (1,0) [Byte]										
		•	•	•	•		•	•	•							
	Status Request	4	100			<status type=""></status>		<returns> with header</returns>	and master address in front (00 00 00 00 FF 00 00 01 Length Data)							
	Camera Enable	4	100	64	0	Value Type [Byte]	True/False (1,0)									
	Exposing now?	4	101	65	0	Value Type [Byte]	True/False (1,0)									
	Trigger Time	4	102	66	0	Value Type (Ulong)	Exposure Time (mS)									
	Focus Time	4	103	67	0	Value Type [Uint]	Focus Time (mS)									
	Max Shots	4	104	68	0	Value Type (Ulong)		Count								
	Exposure Delay	4	105	69	0	Value Type [Uint]	Delay (m									
	Focus w Shutter	4	106	6A	0	Value Type [Byte]	1, 0									
	Mirror Up (Repeat Shot)	4	107	6B	0	Value Type [Byte]	True/False (1,0)									1
	Interval Time	4	108	6C	0	Value Type [Ulong]	lr	nterval Time (mS)								
Number of shots that have been taken s far during the current program.	Current Snots	4	109	6D	0	Value Type [Uint]	Number of sho	ts taken								
	Camera Test Mode	4	110	6E	0	Value Type [Byte]	True/False (1.0)									

			Address	Sub-Address	Command	Data Length	Data
Broadcasts	These function the same as the start, stop.	Start	1	0	1	0	
	and pause commands above, but can be	Stop	1	0	2	0	
	used to synchronize movement of multiple controllers.	Pause	1	0	3	0	
	Use this to assign an address to a controller with an unknown address. Don't use when controllers are daisy-chained together.	Assign Address	1	0	4	1	2-255

Note: nodes do not give a response to broadcast commands.

Query Value Types	
0	Byte
1	Unsigned Int
2	Int
3	Long
4	Unsigned Long
5	Float
6	String

The floats are actually fixed points. They are multiplied by 100 and transmitted as longs, so they need to be divided by 100 on the master side to resolve the true value.