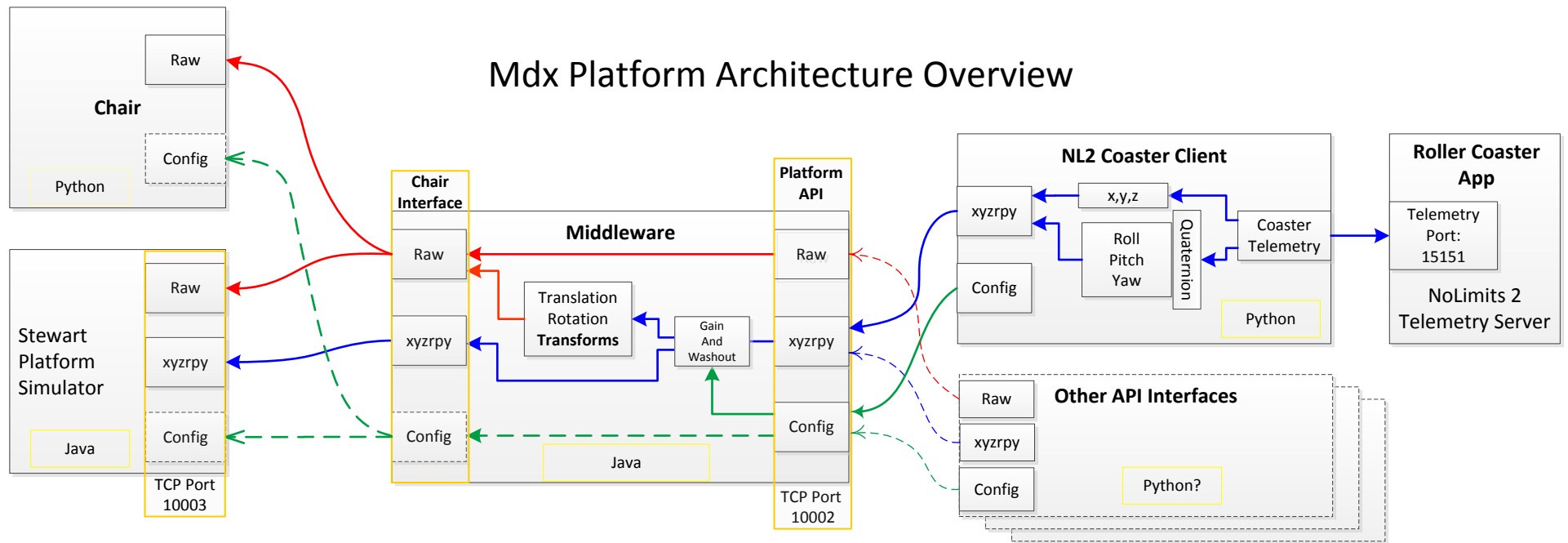


# Mdx Platform Architecture Overview



## Movement methods:

### Method identifier:

- "raw" - array of raw values indicating length of six muscles
- "xyzrpy" - array of six values for xyz translations & rotations
  - x translation is forward/backward movement (surge)
  - y translation is side to side movement (sway)
  - z translation is up/down movement (heave)
  - x rotation is tilting on front/back axis (roll)
  - y rotation is tilting on lateral axis (pitch)
  - z rotation is tilting on vertical axis (yaw)

arguments default to normalized values (range between  $\pm 1.0$ )  
 In future, "units": "real" can be included in message to provide real world mm values for translation, degrees for rotation

args: An array of six floating point values

Example: cmd with 10% heave (movement up), -20% roll (bank)  
 {"jsonrpc": "2.0", "method": "xyzrpy", "args": [0.0, 0.0, 0.1, -0.2, 0.0, 0.0]}

## Configuration Method: - identifier "config"

(each of the following arguments is optional)

"blocking" true/false - (currently only supports false)

- "gainX" float multiplier for x values
- "gainY" float multiplier for y values
- "gainZ" float multiplier for z values
- "gainRoll" float multiplier for roll values
- "gainPitch" float multiplier for pitch values
- "gainYaw" float multiplier for yaw values
- "gain" float multiplier for all 6 DOF
- all above gain factors default to 1.0

- "washoutX" washout factor for x values
- "washoutY" washout factor for y values
- "washoutZ" washout factor for z values
- "washoutRoll" washout factor for roll values
- "washoutPitch" washout factor for pitch values
- "washoutYaw" washout factor for yaw values

- washouts default to 1.0

lower numbers increase the rate values will decay to 0

Example: set overall gain to 0.5 and yaw washout to 0.996  
 {"jsonrpc": "2.0", "method": "config", "gain": 0.5, "washoutYaw": 0.996}

## Get Geometry Method: - identifier "geometry"

(returns physical configuration and capability of the platform)

return values:

- "baseRadius" value in mm
- "baseAngles" array of 6 angles
- "platformRadius" value in mm
- "platformAngles" array of 6 angles
- "actuatorLen" float value in mm
- "maxTranslation" float value in mm
- "maxRotation" float angle in degrees

This message is used by the middleware to get information on chair geometry that is used by the transform logic.

This information can be used by clients to limit movements to achievable values or to scale normalized messages to real world values

Example request:

{"jsonrpc": "2.0", "method": "geometry"}

Example reply fragment:

{"jsonrpc": "2.0", "reply": "geometry", "baseRadius": 400, "baseAngles": [140, 207, 226, 314, 334, 40], ...}