

LS-CAT PGPMAC

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Chapter 1

The LS-CAT pgpmac Project

[pgpmac.c](#)

Some pmac defines, typedefs, functions suggested by Delta Tau Accessory 54E User Manual, October 23, 2003 (C) 2003 by Delta Tau Data Systems, Inc. All rights reserved.

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This project implements the MD2 communications required for operation at LS-CAT and is intended to replace Windows XP based .NET code provided by MAATEL.

The need to do this is driven by a desire to make the system as effecient and fast as possible by combining various operations. A proof-of-principle version of this code saw frame rates of 23/minute as opposed to the nominal 18/minute we normally quote for 1 second exposures.

Additionally, as we rapidly approach EOL for Windows XP an alternative is urgently needed.

Structure

The project is roughly broken down as follows:

lsevents.c	Simple event queue
lsredis.c	Receive key value pair updates from redis databases
lslogging.c	A logging utility to simplify debugging
lspg.c	Handles communications with the controlling posgresql database
lsupdate.c	Periodically update the px.kvs table with new positions.
md2cmds.c	Provides the equivilant (mostly) of the LS-CAT BLUMax code.
pgpmac.c	Main: parses command line and starts up the various threads
pgpmac.h	All includes and defines. The only file included by the .c files in this
pmac_md2_ls-cat.pmc	Code for the PMAC: compile and install with pmac exectutive program.
pmac_md2.sql	Tables and procedures for the posgresql side of the project.

Notes:

- The postgresql and the pmac communications interfaces are asynchronous and rely heavily on the unix "poll" routine.
- The project is multithreaded and based on "pthreads".
- Most threads maintain a queue of commands to simplify communications with each other.
- Note that a MAATEL supported interface for a more recent version of Windows may be available, however, a bit of effort will be required to implement it at LS-CAT as the BLUMax code will likely require some revisions. This is still an option should the present project become intractable.
- An important constraint has been to run the MD2 either from the windows .NET environment or from the pgp-mac environment. A consequence is that the pmac "pmc" file has been augmented to include new capabilities without destroying the code that the .NET interface requires.
- Epics support could come by adapting the "e.c" code to work here directly or could come by making use of the existing kv pair mechanism already in place or, as is most likely, a combination of the two.
- Ncurses support could include input lines for SQL queries and direct commands for supporting homing etc. Perhaps the F keys could change modes or use of special mode changing text commands. Output is not asynchronous. Although this is unlikely to cause a problem I'd hate to have the program hang because terminal output is hung up.
- PG queries come back as text instead of binary. We could reduce the numeric errors by using binary and things would run a tad faster, though it is unlikely anyone would notice or care about the speed.

MD2 Motors and Coordinate Systems

CS	Motor	
1	1	X = Omega
2	17	X = Center X
	18	Y = Center Y
3	2	X = Alignment X
	3	Y = Alignment Y
	4	Z = Alignment Z
--	5	Analyzer
4	6	X = Zoom
5	7	Y = Aperture Y
	8	Z = Aperture Z
	9	U = Capillary Y
	10	V = Capillary Z
	11	W = Scintillator Z
6		(None)
7	19	X = Kappa
	20	Y = Phi

MD2 Motion Programs

before calling, set

M4XX = 1: flag to indicate we are running program XX
P variables as arguments

Program	Description
1	home omega
2	home alignment table X
3	home alignment table Y
4	home alignment table Z
6	home camera zoom
7	home aperture Y
8	home aperture Z
9	home capillary Y
10	home capillary Z
11	home scintillator Z
17	home center X
18	home center Y
19	home kappa
20	home phi (Home position is not defined for phi ...)
25	kappa stress test
26	Combined Incremental move of X and Y in selected coordinate system (Does not reset M426) P170 = X increment P171 = Y increment
31	scan omega P170 = Start P171 = End P173 = Velocity (float) P174 = Sample Rate (I5049) P175 = Acceleration time P176 = Gathering source P177 = Number of passes P178 = Shutter rising distance (units of omega motion) P179 = Shutter falling distance (units of omega motion) P180 = Exposure Time
34	Organ Scan P169 = Motor Number P170 = Start Position P171 = End Position P172 = Step Size P173 = Motor Speed
35	Organ Homing
37	Organ Move (microdiff_hard.ini says we don't use this anymore) P169 = Capillary Z P170 = Scintillator Z P171 = Aperture Z
50	Combined Incremental move of X and Y P170 = X increment P171 = Y increment
52	X oscillation (while M320 == 1) (Does not reset M452)
53	Center X and Y Synchronized homing

54 Combined X, Y, Z absolute move
 P170 = X
 P171 = Y
 P172 = Z

131 LS-CAT Modified Omega Scan
 P170 = Shutter open position, in counts
 P171 = Delta omega, in counts
 P173 = Omega velocity (counts/msec)
 P175 = Acceleration Time (msec)
 P177 = Number of passes
 P178 = Shutter Rising Distance
 P179 = Shutter Falling Distance
 P180 = Exposure Time (msec)

140 LS-CAT Move X Absolute
 Q10 = X Value (cts)

141 LS-CAT Move Y Absolute
 Q11 = Y Value (cts)

142 LS-CAT Move Z Absolute
 Q12 = Z Value (cts)

150 LS-CAT Move X, Y Absolute
 Q20 = X Value
 Q21 = Y Value

160 LS-CAT Move X, Y, Z Absolute
 Q30 = X Value
 Q31 = Y Value
 Q32 = Z Value

Chapter 2

Data Structure Index

2.1 Data Structures

Here are the data structures with brief descriptions:

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Chapter 3

File Index

3.1 File List

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Chapter 4

Data Structure Documentation

4.1 lsevents_listener_struct Struct Reference

Linked list of event listeners.

Data Fields

- struct lsevents_listener_struct * next
Next listener.
- char * raw_regexp
the original string sent to us
- regex_t re
regular expression representing listened for events
- void(* cb)(char *)
call back function

4.1.1 Detailed Description

Linked list of event listeners.

Definition at line 27 of file lsevents.c.

4.1.2 Field Documentation

4.1.2.1 void(* lsevents_listener_struct::cb)(char *)

call back function

Definition at line 31 of file lsevents.c.

4.1.2.2 struct lsevents_listener_struct* lsevents_listener_struct::next

Next listener.

Definition at line 28 of file lsevents.c.

4.1.2.3 `char* lsevents_listener_struct::raw_regexp`

the original string sent to us

Definition at line 29 of file lsevents.c.

4.1.2.4 `regex_t lsevents_listener_struct::re`

regular expression representing listened for events

Definition at line 30 of file lsevents.c.

The documentation for this struct was generated from the following file:

- [lsevents.c](#)

4.2 lsevents_queue_struct Struct Reference

Storage definition for the events.

Data Fields

- `char event [LSEVENTS_EVENT_LENGTH]`
name of the event

4.2.1 Detailed Description

Storage definition for the events.

Just a string for now. Perhaps one day we'll succumb to the temptation to add an argument or two.

Definition at line 17 of file lsevents.c.

4.2.2 Field Documentation

4.2.2.1 `char lsevents_queue_struct::event[LSEVENTS_EVENT_LENGTH]`

name of the event

Definition at line 18 of file lsevents.c.

The documentation for this struct was generated from the following file:

- [lsevents.c](#)

4.3 lslogging_queue_struct Struct Reference

Our log object: time and message.

Data Fields

- `struct timespec ltime`
time stamp: set when queued

- char [lmsg](#) [[LSLOGGING_MSG_LENGTH](#)]
our message, truncated if too long

4.3.1 Detailed Description

Our log object: time and message.

Definition at line 24 of file `lslogging.c`.

4.3.2 Field Documentation

4.3.2.1 char `lslogging_queue_struct::lmsg`[[LSLOGGING_MSG_LENGTH](#)]

our message, truncated if too long

Definition at line 26 of file `lslogging.c`.

4.3.2.2 struct timespec `lslogging_queue_struct::ltime`

time stamp: set when queued

Definition at line 25 of file `lslogging.c`.

The documentation for this struct was generated from the following file:

- [lslogging.c](#)

4.4 lspg_getcenter_struct Struct Reference

Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.

```
#include <pgpmac.h>
```

Data Fields

- pthread_mutex_t [mutex](#)
don't let the threads collide!
- pthread_cond_t [cond](#)
provides signaling for when the query is done
- int [new_value_ready](#)
used with condition
- int [no_rows_returned](#)
flag in case no centering information was forthcoming
- int [zoom](#)
the next zoom level to go to before taking the next movie
- int [zoom_isnull](#)
- double [dcx](#)
center x change
- int [dcx_isnull](#)
- double [dcy](#)
center y change
- int [dcy_isnull](#)
- double [dax](#)

alignment x change

- int [dax_isnull](#)
- double [day](#)

alignment y change

- int [day_isnull](#)
- double [daz](#)

alignment z change

- int [daz_isnull](#)

4.4.1 Detailed Description

Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.

Definition at line 165 of file pgpmac.h.

4.4.2 Field Documentation

4.4.2.1 pthread_cond_t lspg_getcenter_struct::cond

provides signaling for when the query is done

Definition at line 167 of file pgpmac.h.

4.4.2.2 double lspg_getcenter_struct::dax

alignment x change

Definition at line 180 of file pgpmac.h.

4.4.2.3 int lspg_getcenter_struct::dax_isnull

Definition at line 181 of file pgpmac.h.

4.4.2.4 double lspg_getcenter_struct::day

alignment y change

Definition at line 183 of file pgpmac.h.

4.4.2.5 int lspg_getcenter_struct::day_isnull

Definition at line 184 of file pgpmac.h.

4.4.2.6 double lspg_getcenter_struct::daz

alignment z change

Definition at line 186 of file pgpmac.h.

4.4.2.7 int lspg_getcenter_struct::daz_isnull

Definition at line 187 of file pgpmac.h.

4.4.2.8 double lspg_getcenter_struct::dcx

center x change

Definition at line 174 of file pgpmac.h.

4.4.2.9 int lspg_getcenter_struct::dcx_isnull

Definition at line 175 of file pgpmac.h.

4.4.2.10 double lspg_getcenter_struct::dcy

center y change

Definition at line 177 of file pgpmac.h.

4.4.2.11 int lspg_getcenter_struct::dcy_isnull

Definition at line 178 of file pgpmac.h.

4.4.2.12 pthread_mutex_t lspg_getcenter_struct::mutex

don't let the threads collide!

Definition at line 166 of file pgpmac.h.

4.4.2.13 int lspg_getcenter_struct::new_value_ready

used with condition

Definition at line 168 of file pgpmac.h.

4.4.2.14 int lspg_getcenter_struct::no_rows_returned

flag in case no centering information was forthcoming

Definition at line 169 of file pgpmac.h.

4.4.2.15 int lspg_getcenter_struct::zoom

the next zoom level to go to before taking the next movie

Definition at line 171 of file pgpmac.h.

4.4.2.16 int lspg_getcenter_struct::zoom_isnull

Definition at line 172 of file pgpmac.h.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.5 lspg_lock_detector_struct Struct Reference

lock detector object Implements detector lock for exposure control

Data Fields

- pthread_mutex_t [mutex](#)
- pthread_cond_t [cond](#)
- int [new_value_ready](#)

4.5.1 Detailed Description

lock detector object Implements detector lock for exposure control

Definition at line 831 of file lspg.c.

4.5.2 Field Documentation

4.5.2.1 pthread_cond_t lspg_lock_detector_struct::cond

Definition at line 833 of file lspg.c.

4.5.2.2 pthread_mutex_t lspg_lock_detector_struct::mutex

Definition at line 832 of file lspg.c.

4.5.2.3 int lspg_lock_detector_struct::new_value_ready

Definition at line 834 of file lspg.c.

The documentation for this struct was generated from the following file:

- [lspg.c](#)

4.6 lspg_lock_diffractionmeter_struct Struct Reference

Object used to impliment locking the diffractometer Critical to exposure timing.

Data Fields

- pthread_mutex_t [mutex](#)
- pthread_cond_t [cond](#)
- int [new_value_ready](#)

4.6.1 Detailed Description

Object used to impliment locking the diffractometer Critical to exposure timing.

Definition at line 772 of file lspg.c.

4.6.2 Field Documentation

4.6.2.1 pthread_cond_t lspg_lock_diffractionmeter_struct::cond

Definition at line 774 of file lspg.c.

4.6.2.2 pthread_mutex_t lspg_lock_diffractionmeter_struct::mutex

Definition at line 773 of file lspg.c.

4.6.2.3 int lspg_lock_diffractionmeter_struct::new_value_ready

Definition at line 775 of file lspg.c.

The documentation for this struct was generated from the following file:

- [lspg.c](#)

4.7 lspg_nextshot_struct Struct Reference

Storage definition for nextshot query.

```
#include <pgpmac.h>
```

Data Fields

- pthread_mutex_t [mutex](#)
Our mutex for sanity in the multi-threaded program.
- pthread_cond_t [cond](#)
Condition to wait for a response from our postgresql server.
- int [new_value_ready](#)
Our flag for the condition to wait for.
- int [no_rows_returned](#)
flag indicating that no rows were returned.
- char * [dsdir](#)
Directory for data relative to the ESAF home directory.
- int [dsdir_isnull](#)
- char * [dspid](#)
ID string identifying this dataset.
- int [dspid_isnull](#)
- double [dsowidth](#)
dataset defined oscillation width
- int [dsowidth_isnull](#)
- char * [dsoscaxis](#)
dataset defined oscillation axis (always omega)
- int [dsoscaxis_isnull](#)
- double [dsexp](#)
dataset defined exposure time
- int [dsexp_isnull](#)
- long long [skey](#)
key identifying a particular image
- int [skey_isnull](#)
- double [sstart](#)
starting angle
- int [sstart_isnull](#)
- char * [sfn](#)
file name
- int [sfn_isnull](#)

- double [dsphi](#)
dataset defined starting phi angle
- int [dsphi_isnull](#)
- double [dsomega](#)
dataset defined starting omega angle
- int [dsomega_isnull](#)
- double [dskappa](#)
dataset defined starting kappa angle
- int [dskappa_isnull](#)
- double [dsdist](#)
dataset defined detector distance
- int [dsdist_isnull](#)
- double [dsnrg](#)
dataset defined energy
- int [dsnrg_isnull](#)
- unsigned int [dshpid](#)
sample holder ID
- int [dshpid_isnull](#)
- double [cx](#)
centering table x position
- int [cx_isnull](#)
- double [cy](#)
centering table y position
- int [cy_isnull](#)
- double [ax](#)
alignment table x position
- int [ax_isnull](#)
- double [ay](#)
alignment table y position
- int [ay_isnull](#)
- double [az](#)
alignment table z position
- int [az_isnull](#)
- int [active](#)
flag: 1=move to indicated center position, 0=don't move center or alignment tables
- int [active_isnull](#)
- int [sindex](#)
index of frame (used to generate the file extension)
- int [sindex_isnull](#)
- char * [stype](#)
"Normal" or "Gridsearch"
- int [stype_isnull](#)
- double [dsowidth2](#)
next image oscillation width
- int [dsowidth2_isnull](#)
- char * [dsoscaxis2](#)
next image oscillation axis (always "omega")
- int [dsoscaxis2_isnull](#)
- double [dsexp2](#)
next image exposure time
- int [dsexp2_isnull](#)
- double [sstart2](#)

- next image start angle*
 - int [sstart2_isnull](#)
 - double [dsphi2](#)
- next image phi position*
 - int [dsphi2_isnull](#)
 - double [dsomega2](#)
- next image omega position*
 - int [dsomega2_isnull](#)
 - double [dskappa2](#)
- next image kappa position*
 - int [dskappa2_isnull](#)
 - double [dsdist2](#)
- next image distance*
 - int [dsdist2_isnull](#)
 - double [dsnrg2](#)
- next image energy*
 - int [dsnrg2_isnull](#)
 - double [cx2](#)
- next image centering table x position*
 - int [cx2_isnull](#)
 - double [cy2](#)
- next image centering table y position*
 - int [cy2_isnull](#)
 - double [ax2](#)
- next image alignment x position*
 - int [ax2_isnull](#)
 - double [ay2](#)
- next image alignment y position*
 - int [ay2_isnull](#)
 - double [az2](#)
- next image alignment z position*
 - int [az2_isnull](#)
 - int [active2](#)
- flag: 1 if next image should use the above centering parameters*
 - int [active2_isnull](#)
 - int [sindex2](#)
- next image index number*
 - int [sindex2_isnull](#)
 - char * [stype2](#)
- next image type ("Normal" or "Gridsearch")*
 - int [stype2_isnull](#)

4.7.1 Detailed Description

Storage definition for nextshot query.

The next shot query returns all the information needed to collect the next data frame. Since SQL allows for null fields independently from blank strings a separate integer is used as a flag for this case. This adds to the program complexity but allows for some important cases. Suck it up.

Definition at line 201 of file pgpmac.h.

4.7.2 Field Documentation

4.7.2.1 `int lspg_nextshot_struct::active`

flag: 1=move to indicated center position, 0=don't move center or alignment tables

Definition at line 264 of file pgpmac.h.

4.7.2.2 `int lspg_nextshot_struct::active2`

flag: 1 if next image should use the above centering parameters

Definition at line 315 of file pgpmac.h.

4.7.2.3 `int lspg_nextshot_struct::active2_isnull`

Definition at line 316 of file pgpmac.h.

4.7.2.4 `int lspg_nextshot_struct::active_isnull`

Definition at line 265 of file pgpmac.h.

4.7.2.5 `double lspg_nextshot_struct::ax`

alignment table x position

Definition at line 255 of file pgpmac.h.

4.7.2.6 `double lspg_nextshot_struct::ax2`

next image alignment x position

Definition at line 306 of file pgpmac.h.

4.7.2.7 `int lspg_nextshot_struct::ax2_isnull`

Definition at line 307 of file pgpmac.h.

4.7.2.8 `int lspg_nextshot_struct::ax_isnull`

Definition at line 256 of file pgpmac.h.

4.7.2.9 `double lspg_nextshot_struct::ay`

alignment table y position

Definition at line 258 of file pgpmac.h.

4.7.2.10 `double lspg_nextshot_struct::ay2`

next image alignment y position

Definition at line 309 of file pgpmac.h.

4.7.2.11 int lspg_nextshot_struct::ay2_isnull

Definition at line 310 of file pgpmac.h.

4.7.2.12 int lspg_nextshot_struct::ay_isnull

Definition at line 259 of file pgpmac.h.

4.7.2.13 double lspg_nextshot_struct::az

alignment table z position

Definition at line 261 of file pgpmac.h.

4.7.2.14 double lspg_nextshot_struct::az2

next image alignment z position

Definition at line 312 of file pgpmac.h.

4.7.2.15 int lspg_nextshot_struct::az2_isnull

Definition at line 313 of file pgpmac.h.

4.7.2.16 int lspg_nextshot_struct::az_isnull

Definition at line 262 of file pgpmac.h.

4.7.2.17 pthread_cond_t lspg_nextshot_struct::cond

Condition to wait for a response from our postgresql server.

Definition at line 203 of file pgpmac.h.

4.7.2.18 double lspg_nextshot_struct::cx

centering table x position

Definition at line 249 of file pgpmac.h.

4.7.2.19 double lspg_nextshot_struct::cx2

next image centering table x position

Definition at line 300 of file pgpmac.h.

4.7.2.20 int lspg_nextshot_struct::cx2_isnull

Definition at line 301 of file pgpmac.h.

4.7.2.21 int lspg_nextshot_struct::cx_isnull

Definition at line 250 of file pgpmac.h.

4.7.2.22 `double lspg_nextshot_struct::cy`

centering table y position

Definition at line 252 of file pgpmac.h.

4.7.2.23 `double lspg_nextshot_struct::cy2`

next image centering table y position

Definition at line 303 of file pgpmac.h.

4.7.2.24 `int lspg_nextshot_struct::cy2_isnull`

Definition at line 304 of file pgpmac.h.

4.7.2.25 `int lspg_nextshot_struct::cy_isnull`

Definition at line 253 of file pgpmac.h.

4.7.2.26 `char* lspg_nextshot_struct::dsdir`

Directory for data relative to the ESAF home directory.

Definition at line 207 of file pgpmac.h.

4.7.2.27 `int lspg_nextshot_struct::dsdir_isnull`

Definition at line 208 of file pgpmac.h.

4.7.2.28 `double lspg_nextshot_struct::dsdist`

dataset defined detector distance

Definition at line 240 of file pgpmac.h.

4.7.2.29 `double lspg_nextshot_struct::dsdist2`

next image distance

Definition at line 294 of file pgpmac.h.

4.7.2.30 `int lspg_nextshot_struct::dsdist2_isnull`

Definition at line 295 of file pgpmac.h.

4.7.2.31 `int lspg_nextshot_struct::dsdist_isnull`

Definition at line 241 of file pgpmac.h.

4.7.2.32 double lspg_nextshot_struct::dsexp

dataset defined exposure time

Definition at line 219 of file pgpmac.h.

4.7.2.33 double lspg_nextshot_struct::dsexp2

next image exposure time

Definition at line 279 of file pgpmac.h.

4.7.2.34 int lspg_nextshot_struct::dsexp2_isnull

Definition at line 280 of file pgpmac.h.

4.7.2.35 int lspg_nextshot_struct::dsexp_isnull

Definition at line 220 of file pgpmac.h.

4.7.2.36 unsigned int lspg_nextshot_struct::dshpid

sample holder ID

Definition at line 246 of file pgpmac.h.

4.7.2.37 int lspg_nextshot_struct::dshpid_isnull

Definition at line 247 of file pgpmac.h.

4.7.2.38 double lspg_nextshot_struct::dskappa

dataset defined starting kappa angle

Definition at line 237 of file pgpmac.h.

4.7.2.39 double lspg_nextshot_struct::dskappa2

next image kappa position

Definition at line 291 of file pgpmac.h.

4.7.2.40 int lspg_nextshot_struct::dskappa2_isnull

Definition at line 292 of file pgpmac.h.

4.7.2.41 int lspg_nextshot_struct::dskappa_isnull

Definition at line 238 of file pgpmac.h.

4.7.2.42 double lspg_nextshot_struct::dsnrg

dataset defined energy

Definition at line 243 of file pgpmac.h.

4.7.2.43 double lspg_nextshot_struct::dsnrg2

next image energy

Definition at line 297 of file pgpmac.h.

4.7.2.44 int lspg_nextshot_struct::dsnrg2_isnull

Definition at line 298 of file pgpmac.h.

4.7.2.45 int lspg_nextshot_struct::dsnrg_isnull

Definition at line 244 of file pgpmac.h.

4.7.2.46 double lspg_nextshot_struct::dsomega

dataset defined starting omega angle

Definition at line 234 of file pgpmac.h.

4.7.2.47 double lspg_nextshot_struct::dsomega2

next image omega position

Definition at line 288 of file pgpmac.h.

4.7.2.48 int lspg_nextshot_struct::dsomega2_isnull

Definition at line 289 of file pgpmac.h.

4.7.2.49 int lspg_nextshot_struct::dsomega_isnull

Definition at line 235 of file pgpmac.h.

4.7.2.50 char* lspg_nextshot_struct::dsoscaxis

dataset defined oscillation axis (always omega)

Definition at line 216 of file pgpmac.h.

4.7.2.51 char* lspg_nextshot_struct::dsoscaxis2

next image ascillation axis (always "omega")

Definition at line 276 of file pgpmac.h.

4.7.2.52 int lspg_nextshot_struct::dsoscaxis2_isnull

Definition at line 277 of file pgpmac.h.

4.7.2.53 int lspg_nextshot_struct::dsoscaxis_isnull

Definition at line 217 of file pgpmac.h.

4.7.2.54 double lspg_nextshot_struct::dsowidth

dataset defined oscillation width

Definition at line 213 of file pgpmac.h.

4.7.2.55 double lspg_nextshot_struct::dsowidth2

next image oscillation width

Definition at line 273 of file pgpmac.h.

4.7.2.56 int lspg_nextshot_struct::dsowidth2_isnull

Definition at line 274 of file pgpmac.h.

4.7.2.57 int lspg_nextshot_struct::dsowidth_isnull

Definition at line 214 of file pgpmac.h.

4.7.2.58 double lspg_nextshot_struct::dsphi

dataset defined starting phi angle

Definition at line 231 of file pgpmac.h.

4.7.2.59 double lspg_nextshot_struct::dsphi2

next image phi position

Definition at line 285 of file pgpmac.h.

4.7.2.60 int lspg_nextshot_struct::dsphi2_isnull

Definition at line 286 of file pgpmac.h.

4.7.2.61 int lspg_nextshot_struct::dsphi_isnull

Definition at line 232 of file pgpmac.h.

4.7.2.62 char* lspg_nextshot_struct::dspid

ID string identifying this dataset.

Definition at line 210 of file pgpmac.h.

4.7.2.63 `int lspg_nextshot_struct::dspid_isnull`

Definition at line 211 of file pgpmac.h.

4.7.2.64 `pthread_mutex_t lspg_nextshot_struct::mutex`

Our mutex for sanity in the multi-threaded program.

Definition at line 202 of file pgpmac.h.

4.7.2.65 `int lspg_nextshot_struct::new_value_ready`

Our flag for the condition to wait for.

Definition at line 204 of file pgpmac.h.

4.7.2.66 `int lspg_nextshot_struct::no_rows_returned`

flag indicating that no rows were returned.

Definition at line 205 of file pgpmac.h.

4.7.2.67 `char* lspg_nextshot_struct::sfn`

file name

Definition at line 228 of file pgpmac.h.

4.7.2.68 `int lspg_nextshot_struct::sfn_isnull`

Definition at line 229 of file pgpmac.h.

4.7.2.69 `int lspg_nextshot_struct::sindex`

index of frame (used to generate the file extension)

Definition at line 267 of file pgpmac.h.

4.7.2.70 `int lspg_nextshot_struct::sindex2`

next image index number

Definition at line 318 of file pgpmac.h.

4.7.2.71 `int lspg_nextshot_struct::sindex2_isnull`

Definition at line 319 of file pgpmac.h.

4.7.2.72 `int lspg_nextshot_struct::sindex_isnull`

Definition at line 268 of file pgpmac.h.

4.7.2.73 long long lspg_nextshot_struct::skey

key identifying a particular image

Definition at line 222 of file pgpmac.h.

4.7.2.74 int lspg_nextshot_struct::skey_isnull

Definition at line 223 of file pgpmac.h.

4.7.2.75 double lspg_nextshot_struct::sstart

starting angle

Definition at line 225 of file pgpmac.h.

4.7.2.76 double lspg_nextshot_struct::sstart2

next image start angle

Definition at line 282 of file pgpmac.h.

4.7.2.77 int lspg_nextshot_struct::sstart2_isnull

Definition at line 283 of file pgpmac.h.

4.7.2.78 int lspg_nextshot_struct::sstart_isnull

Definition at line 226 of file pgpmac.h.

4.7.2.79 char* lspg_nextshot_struct::stype

"Normal" or "Gridsearch"

Definition at line 270 of file pgpmac.h.

4.7.2.80 char* lspg_nextshot_struct::stype2

next image type ("Normal" or "Gridsearch")

Definition at line 321 of file pgpmac.h.

4.7.2.81 int lspg_nextshot_struct::stype2_isnull

Definition at line 322 of file pgpmac.h.

4.7.2.82 int lspg_nextshot_struct::stype_isnull

Definition at line 271 of file pgpmac.h.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.8 lspg_seq_run_prep_struct Struct Reference

Data collection running object.

Data Fields

- pthread_mutex_t [mutex](#)
- pthread_cond_t [cond](#)
- int [new_value_ready](#)

4.8.1 Detailed Description

Data collection running object.

Definition at line 889 of file lspg.c.

4.8.2 Field Documentation

4.8.2.1 pthread_cond_t lspg_seq_run_prep_struct::cond

Definition at line 891 of file lspg.c.

4.8.2.2 pthread_mutex_t lspg_seq_run_prep_struct::mutex

Definition at line 890 of file lspg.c.

4.8.2.3 int lspg_seq_run_prep_struct::new_value_ready

Definition at line 892 of file lspg.c.

The documentation for this struct was generated from the following file:

- [lspg.c](#)

4.9 lspg_wait_for_detector_struct Struct Reference

Object that implements detector / spindle timing We use database locks for exposure control and this implements the md2 portion of this handshake.

Data Fields

- pthread_mutex_t [mutex](#)
- pthread_cond_t [cond](#)
- int [new_value_ready](#)

4.9.1 Detailed Description

Object that implements detector / spindle timing We use database locks for exposure control and this implements the md2 portion of this handshake.

Definition at line 707 of file lspg.c.

4.9.2 Field Documentation

4.9.2.1 pthread_cond_t lspg_wait_for_detector_struct::cond

Definition at line 709 of file lspg.c.

4.9.2.2 pthread_mutex_t lspg_wait_for_detector_struct::mutex

Definition at line 708 of file lspg.c.

4.9.2.3 int lspg_wait_for_detector_struct::new_value_ready

Definition at line 710 of file lspg.c.

The documentation for this struct was generated from the following file:

- [lspg.c](#)

4.10 lspgQueryQueueStruct Struct Reference

Store each query along with it's callback function.

Data Fields

- char [qs](#) [[LS_PG_QUERY_STRING_LENGTH](#)]
our queries should all be pretty short as we'll just be calling functions: fixed length here simplifies memory management
- void(* [onResponse](#))(struct [lspgQueryQueueStruct](#) *qq, PGresult *pgr)
Callback function for when a query returns a result.

4.10.1 Detailed Description

Store each query along with it's callback function.

All calls are asynchronous

Definition at line 31 of file kvredis.c.

4.10.2 Field Documentation

4.10.2.1 void(* lspgQueryQueueStruct::onResponse)(struct lspgQueryQueueStruct *qq, PGresult *pgr)

Callback function for when a query returns a result.

Definition at line 33 of file kvredis.c.

4.10.2.2 char lspgQueryQueueStruct::qs

our queries should all be pretty short as we'll just be calling functions: fixed length here simplifies memory management

Definition at line 32 of file kvredis.c.

The documentation for this struct was generated from the following files:

- [kvredis.c](#)
- [lspg.c](#)

4.11 Ispmac_bi_struct Struct Reference

Storage for binary inputs.

```
#include <pgpmac.h>
```

Data Fields

- int * [ptr](#)
points to the location in the status buffer
- pthread_mutex_t [mutex](#)
so we don't get confused
- int [mask](#)
mask for the bit in the status register
- int [previous](#)
the previous value
- int [first_time](#)
flag indicating we've not read the input even once
- char * [changeEventOn](#)
Event to send when the value changes to 1.
- char * [changeEventOff](#)
Event to send when the value changes to 0.

4.11.1 Detailed Description

Storage for binary inputs.

Definition at line 148 of file pgpmac.h.

4.11.2 Field Documentation

4.11.2.1 char* Ispmac_bi_struct::changeEventOff

Event to send when the value changes to 0.

Definition at line 155 of file pgpmac.h.

4.11.2.2 char* Ispmac_bi_struct::changeEventOn

Event to send when the value changes to 1.

Definition at line 154 of file pgpmac.h.

4.11.2.3 int Ispmac_bi_struct::first_time

flag indicating we've not read the input even once

Definition at line 153 of file pgpmac.h.

4.11.2.4 `int lspmac_bi_struct::mask`

mask for the bit in the status register

Definition at line 151 of file `pgpmac.h`.

4.11.2.5 `pthread_mutex_t lspmac_bi_struct::mutex`

so we don't get confused

Definition at line 150 of file `pgpmac.h`.

4.11.2.6 `int lspmac_bi_struct::previous`

the previous value

Definition at line 152 of file `pgpmac.h`.

4.11.2.7 `int* lspmac_bi_struct::ptr`

points to the location in the status buffer

Definition at line 149 of file `pgpmac.h`.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.12 `lspmac_cmd_queue_struct` Struct Reference

PMAC command queue item.

```
#include <pgpmac.h>
```

Data Fields

- [pmac_cmd_t pcmd](#)
the pmac command to send
- `int no_reply`
1 = no reply is expected, 0 = expect a reply
- `struct timespec time_sent`
time this item was dequeued and sent to the pmac
- `unsigned char rbuff [1400]`
buffer for the returned bytes
- `void(* onResponse)(struct lspmac_cmd_queue_struct *, int, unsigned char *)`
function to call when response is received. args are (int fd, nreturned, buffer)

4.12.1 Detailed Description

PMAC command queue item.

Command queue items are fixed length to simplify memory management.

Definition at line 85 of file `pgpmac.h`.

4.12.2 Field Documentation

4.12.2.1 `int lspmac_cmd_queue_struct::no_reply`

1 = no reply is expected, 0 = expect a reply

Definition at line 87 of file `pgpmac.h`.

4.12.2.2 `void(* lspmac_cmd_queue_struct::onResponse)(struct lspmac_cmd_queue_struct *, int, unsigned char *)`

function to call when response is received. args are (int fd, nreturned, buffer)

Definition at line 90 of file `pgpmac.h`.

4.12.2.3 `pmac_cmd_t lspmac_cmd_queue_struct::pcmd`

the pmac command to send

Definition at line 86 of file `pgpmac.h`.

4.12.2.4 `unsigned char lspmac_cmd_queue_struct::rbuff[1400]`

buffer for the returned bytes

Definition at line 89 of file `pgpmac.h`.

4.12.2.5 `struct timespec lspmac_cmd_queue_struct::time_sent`

time this item was dequeued and sent to the pmac

Definition at line 88 of file `pgpmac.h`.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.13 `lspmac_motor_struct` Struct Reference

Motor information.

```
#include <pgpmac.h>
```

Data Fields

- `pthread_mutex_t` [mutex](#)
coordinate waiting for motor to be done
- `pthread_cond_t` [cond](#)
used to signal when a motor is done moving
- `int` [not_done](#)
set to 1 when request is queued, zero after motion has toggled
- `void(*` [read](#) `)(struct` [lspmac_motor_struct](#) `*)`
method to read the motor status and position
- `int` [motion_seen](#)
set to 1 when motion has been verified to have started

- struct [lspmac_cmd_queue_struct](#) * [pq](#)
the queue item requesting motion. Used to check time request was made
- int [homing](#)
Homing routine started.
- int [requested_pos_cnts](#)
requested position
- int * [actual_pos_cnts_p](#)
pointer to the md2_status structure to the actual position
- int [actual_pos_cnts](#)
local copy of actual counts so only our mutex is needed to read
- double [position](#)
scaled position
- double [reported_position](#)
previous position reported to the database
- double [requested_position](#)
The position as requested by the user.
- int * [status1_p](#)
First 24 bit PMAC motor status word.
- int [status1](#)
local copy of status1
- int * [status2_p](#)
Second 24 bit PMAC motor status word.
- int [status2](#)
local copy of status2
- char [statuss](#) [64]
short text summarizing status
- char * [dac_mvar](#)
controlling mvariable as a string
- char * [name](#)
Name of motor as referred by ls database kvs table.
- [lsredis_obj_t](#) * [unit](#)
string to use as the units
- [lsredis_obj_t](#) * [printf_fmt](#)
printf format
- [lsredis_obj_t](#) * [redis_fmt](#)
special format string to create text array for putting the position back into redis
- [lsredis_obj_t](#) * [max_speed](#)
our maximum speed (cts/msec)
- [lsredis_obj_t](#) * [max_accel](#)
our maximum acceleration (cts/msec²)
- [lsredis_obj_t](#) * [motor_num](#)
pmac motor number
- [lsredis_obj_t](#) * [coord_num](#)
coordinate system this motor belongs to (0 if none)
- [lsredis_obj_t](#) * [update_resolution](#)
Change needs to be at least this big to report as a new position to the database.
- [lsredis_obj_t](#) * [axis](#)
the axis (X, Y, Z, etc) or null if not in a coordinate system
- [lsredis_obj_t](#) * [home](#)
pmac commands to home motor
- [lsredis_obj_t](#) * [active](#)

- Use the motor ("true") or not ("false")*
- `lsredis_obj_t * active_init`
 - pmac commands to make this motor active*
- `lsredis_obj_t * inactive_init`
 - pmac commands to inactivate the motor*
- `char * write_fmt`
 - Format string to write requested position to PMAC used for binary io.*
- `int * read_ptr`
 - With read_mask finds bit to read for binary i/o.*
- `int read_mask`
 - With read_ptr find bit to read for binary i/o.*
- `void(* moveAbs)(struct lspmac_motor_struct *, double)`
 - function to move the motor*
- `lsredis_obj_t * u2c`
 - conversion from counts to units: 0.0 means not loaded yet*
- `double * lut`
 - lookup table (instead of u2c)*
- `int nlut`
 - length of lut*
- `WINDOW * win`
 - our ncurses window*

4.13.1 Detailed Description

Motor information.

A catchall for motors and motor like objects. Not all members are used by all objects.

Definition at line 100 of file pgpmac.h.

4.13.2 Field Documentation

4.13.2.1 `lsredis_obj_t* lspmac_motor_struct::active`

Use the motor ("true") or not ("false")

Definition at line 132 of file pgpmac.h.

4.13.2.2 `lsredis_obj_t* lspmac_motor_struct::active_init`

pmac commands to make this motor active

Definition at line 133 of file pgpmac.h.

4.13.2.3 `int lspmac_motor_struct::actual_pos_cnts`

local copy of actual counts so only our mutex is needed to read

Definition at line 111 of file pgpmac.h.

4.13.2.4 `int* lspmac_motor_struct::actual_pos_cnts_p`

pointer to the md2_status structure to the actual position

Definition at line 110 of file pgpmac.h.

4.13.2.5 lsredis_obj_t* lspmac_motor_struct::axis

the axis (X, Y, Z, etc) or null if not in a coordinate system

Definition at line 130 of file pgpmac.h.

4.13.2.6 pthread_cond_t lspmac_motor_struct::cond

used to signal when a motor is done moving

Definition at line 102 of file pgpmac.h.

4.13.2.7 lsredis_obj_t* lspmac_motor_struct::coord_num

coordinate system this motor belongs to (0 if none)

Definition at line 128 of file pgpmac.h.

4.13.2.8 char* lspmac_motor_struct::dac.mvar

controlling mvariable as a string

Definition at line 120 of file pgpmac.h.

4.13.2.9 lsredis_obj_t* lspmac_motor_struct::home

pmac commands to home motor

Definition at line 131 of file pgpmac.h.

4.13.2.10 int lspmac_motor_struct::homing

Homing routine started.

Definition at line 108 of file pgpmac.h.

4.13.2.11 lsredis_obj_t* lspmac_motor_struct::inactive_init

pmac commands to inactivate the motor

Definition at line 134 of file pgpmac.h.

4.13.2.12 double* lspmac_motor_struct::lut

lookup table (instead of u2c)

Definition at line 140 of file pgpmac.h.

4.13.2.13 lsredis_obj_t* lspmac_motor_struct::max_accel

our maximum acceleration (cts/msec²)

Definition at line 126 of file pgpmac.h.

4.13.2.14 `lsredis_obj_t* lspmac_motor_struct::max_speed`

our maximum speed (cts/msec)

Definition at line 125 of file pgpmac.h.

4.13.2.15 `int lspmac_motor_struct::motion_seen`

set to 1 when motion has been verified to have started

Definition at line 105 of file pgpmac.h.

4.13.2.16 `lsredis_obj_t* lspmac_motor_struct::motor_num`

pmac motor number

Definition at line 127 of file pgpmac.h.

4.13.2.17 `void(* lspmac_motor_struct::moveAbs)(struct lspmac_motor_struct *, double)`

function to move the motor

Definition at line 138 of file pgpmac.h.

4.13.2.18 `pthread_mutex_t lspmac_motor_struct::mutex`

coordinate waiting for motor to be done

Definition at line 101 of file pgpmac.h.

4.13.2.19 `char* lspmac_motor_struct::name`

Name of motor as referred by ls database kvs table.

Definition at line 121 of file pgpmac.h.

4.13.2.20 `int lspmac_motor_struct::nlut`

length of lut

Definition at line 141 of file pgpmac.h.

4.13.2.21 `int lspmac_motor_struct::not_done`

set to 1 when request is queued, zero after motion has toggled

Definition at line 103 of file pgpmac.h.

4.13.2.22 `double lspmac_motor_struct::position`

scaled position

Definition at line 112 of file pgpmac.h.

4.13.2.23 struct Ispmac_cmd_queue_struct* Ispmac_motor_struct::pq

the queue item requesting motion. Used to check time request was made
Definition at line 106 of file pgpmac.h.

4.13.2.24 Isredis_obj_t* Ispmac_motor_struct::printf_fmt

printf format

Definition at line 123 of file pgpmac.h.

4.13.2.25 void(* Ispmac_motor_struct::read)(struct Ispmac_motor_struct *)

method to read the motor status and position

Definition at line 104 of file pgpmac.h.

4.13.2.26 int Ispmac_motor_struct::read_mask

With read_ptr find bit to read for binary i/o.

Definition at line 137 of file pgpmac.h.

4.13.2.27 int* Ispmac_motor_struct::read_ptr

With read_mask finds bit to read for binary i/o.

Definition at line 136 of file pgpmac.h.

4.13.2.28 Isredis_obj_t* Ispmac_motor_struct::redis_fmt

special format string to create text array for putting the position back into redis

Definition at line 124 of file pgpmac.h.

4.13.2.29 double Ispmac_motor_struct::reported_position

previous position reported to the database

Definition at line 113 of file pgpmac.h.

4.13.2.30 int Ispmac_motor_struct::requested_pos_cnts

requested position

Definition at line 109 of file pgpmac.h.

4.13.2.31 double Ispmac_motor_struct::requested_position

The position as requested by the user.

Definition at line 114 of file pgpmac.h.

4.13.2.32 `int lspmac_motor_struct::status1`

local copy of status1

Definition at line 116 of file pgpmac.h.

4.13.2.33 `int* lspmac_motor_struct::status1_p`

First 24 bit PMAC motor status word.

Definition at line 115 of file pgpmac.h.

4.13.2.34 `int lspmac_motor_struct::status2`

local copy of status2

Definition at line 118 of file pgpmac.h.

4.13.2.35 `int* lspmac_motor_struct::status2_p`

Second 24 bit PMAC motor status word.

Definition at line 117 of file pgpmac.h.

4.13.2.36 `char lspmac_motor_struct::statuss[64]`

short text summarizing status

Definition at line 119 of file pgpmac.h.

4.13.2.37 `lsredis_obj_t* lspmac_motor_struct::u2c`

conversion from counts to units: 0.0 means not loaded yet

Definition at line 139 of file pgpmac.h.

4.13.2.38 `lsredis_obj_t* lspmac_motor_struct::unit`

string to use as the units

Definition at line 122 of file pgpmac.h.

4.13.2.39 `lsredis_obj_t* lspmac_motor_struct::update_resolution`

Change needs to be at least this big to report as a new position to the database.

Definition at line 129 of file pgpmac.h.

4.13.2.40 `WINDOW* lspmac_motor_struct::win`

our ncurses window

Definition at line 142 of file pgpmac.h.

4.13.2.41 char* lspmac_motor_struct::write_fmt

Format string to write requested position to PMAC used for binary io.

Definition at line 135 of file pgpmac.h.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.14 Isredis_obj_struct Struct Reference

Redis Object Basic object whose value is synchronized with our redis db.

```
#include <pgpmac.h>
```

Data Fields

- pthread_mutex_t [mutex](#)
Don't let anyone use an old value.
- pthread_cond_t [cond](#)
wait for a valid value
- struct Isredis_obj_struct * [next](#)
the next in our list (I guess this is going to be a linked list)
- char [valid](#)
1 if we think the value is good, 0 otherwise
- int [wait_for_me](#)
Number of times we need to see our publication before we start accepting new values.
- char * [key](#)
The redis key for this object.
- char * [events_name](#)
Name used to generate events (normally key without the station id)
- int [value_length](#)
Number of bytes allocated for value (not value's string length)
- char * [value](#)
our value
- double [dvalue](#)
our value as a double
- long int [lvalue](#)
our value as a long
- char ** [avalue](#)
our value as an array of strings
- int [bvalue](#)
our value as a boolean (1 or 0) -1 means we couldn't figure it out
- char [cvalue](#)
just the first character of our value
- int [hits](#)
number of times we've searched for this key

4.14.1 Detailed Description

Redis Object Basic object whose value is synchronized with our redis db.

Definition at line 37 of file pgpmac.h.

4.14.2 Field Documentation

4.14.2.1 `char** lsredis_obj_struct::avalue`

our value as an array of strings

Definition at line 49 of file pgpmac.h.

4.14.2.2 `int lsredis_obj_struct::bvalue`

our value as a boolean (1 or 0) -1 means we couldn't figure it out

Definition at line 50 of file pgpmac.h.

4.14.2.3 `pthread_cond_t lsredis_obj_struct::cond`

wait for a valid value

Definition at line 39 of file pgpmac.h.

4.14.2.4 `char lsredis_obj_struct::cvalue`

just the first character of our value

Definition at line 51 of file pgpmac.h.

4.14.2.5 `double lsredis_obj_struct::dvalue`

our value as a double

Definition at line 47 of file pgpmac.h.

4.14.2.6 `char* lsredis_obj_struct::events_name`

Name used to generate events (normally key without the station id)

Definition at line 44 of file pgpmac.h.

4.14.2.7 `int lsredis_obj_struct::hits`

number of times we've searched for this key

Definition at line 52 of file pgpmac.h.

4.14.2.8 `char* lsredis_obj_struct::key`

The redis key for this object.

Definition at line 43 of file pgpmac.h.

4.14.2.9 `long int lsredis_obj_struct::lvalue`

our value as a long

Definition at line 48 of file pgpmac.h.

4.14.2.10 `pthread_mutex_t lster_timer_obj_struct::mutex`

Don't let anyone use an old value.

Definition at line 38 of file `pgpmac.h`.

4.14.2.11 `struct lster_timer_obj_struct* lster_timer_obj_struct::next`

the next in our list (I guess this is going to be a linked list)

Definition at line 40 of file `pgpmac.h`.

4.14.2.12 `char lster_timer_obj_struct::valid`

1 if we think the value is good, 0 otherwise

Definition at line 41 of file `pgpmac.h`.

4.14.2.13 `char* lster_timer_obj_struct::value`

our value

Definition at line 46 of file `pgpmac.h`.

4.14.2.14 `int lster_timer_obj_struct::value_length`

Number of bytes allocated for value (not value's string length)

Definition at line 45 of file `pgpmac.h`.

4.14.2.15 `int lster_timer_obj_struct::wait_for_me`

Number of times we need to see our publication before we start accepting new values.

Definition at line 42 of file `pgpmac.h`.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

4.15 `lster_timer_list_struct` Struct Reference

Everything we need to know about a timer.

Data Fields

- `int shots`
run this many times: -1 means reload forever, 0 means we are done with this timer and it may be reused
- `unsigned long int ncalls`
track how many times we triggered a callback (like an unsigned long int is really needed)
- `char event [LSEVENTS_EVENT_LENGTH]`
the event to send
- `unsigned long int next_secs`
epoch (seconds) of next alarm

- unsigned long int [next_nsecs](#)
nano seconds of next alarm
- unsigned long int [delay_secs](#)
number of seconds for a periodic delay
- unsigned long int [delay_nsecs](#)
nano seconds of delay
- unsigned long int [last_secs](#)
the last time this timer was triggered
- unsigned long int [last_nsecs](#)
the last time this timer was triggered
- unsigned long int [init_secs](#)
our initialization time
- unsigned long int [init_nsecs](#)
our initialization time

4.15.1 Detailed Description

Everything we need to know about a timer.

Definition at line 22 of file `lstimer.c`.

4.15.2 Field Documentation

4.15.2.1 unsigned long int `lstimer_list_struct::delay_nsecs`

nano seconds of delay

Definition at line 29 of file `lstimer.c`.

4.15.2.2 unsigned long int `lstimer_list_struct::delay_secs`

number of seconds for a periodic delay

Definition at line 28 of file `lstimer.c`.

4.15.2.3 char `lstimer_list_struct::event[LSEVENTS_EVENT_LENGTH]`

the event to send

Definition at line 25 of file `lstimer.c`.

4.15.2.4 unsigned long int `lstimer_list_struct::init_nsecs`

our initialization time

Definition at line 33 of file `lstimer.c`.

4.15.2.5 unsigned long int `lstimer_list_struct::init_secs`

our initialization time

Definition at line 32 of file `lstimer.c`.

4.15.2.6 unsigned long int ltimer_list_struct::last_nsecs

the last time this timer was triggered

Definition at line 31 of file ltimer.c.

4.15.2.7 unsigned long int ltimer_list_struct::last_secs

the last time this timer was triggered

Definition at line 30 of file ltimer.c.

4.15.2.8 unsigned long int ltimer_list_struct::ncalls

track how many times we triggered a callback (like an unsigned long int is really needed)

Definition at line 24 of file ltimer.c.

4.15.2.9 unsigned long int ltimer_list_struct::next_nsecs

nano seconds of next alarm

Definition at line 27 of file ltimer.c.

4.15.2.10 unsigned long int ltimer_list_struct::next_secs

epoch (seconds) of next alarm

Definition at line 26 of file ltimer.c.

4.15.2.11 int ltimer_list_struct::shots

run this many times: -1 means reload forever, 0 means we are done with this timer and it may be reused

Definition at line 23 of file ltimer.c.

The documentation for this struct was generated from the following file:

- [ltimer.c](#)

4.16 md2StatusStruct Struct Reference

The block of memory retrieved in a status request.

Data Fields

- int [dummy1](#)
- int [omega_status_1](#)
- int [alignx_status_1](#)
- int [aligny_status_1](#)
- int [alignz_status_1](#)
- int [analyzer_status_1](#)
- int [zoom_status_1](#)
- int [aperturey_status_1](#)
- int [aperturez_status_1](#)

- int [capy_status_1](#)
- int [capz_status_1](#)
- int [scint_status_1](#)
- int [centerx_status_1](#)
- int [centery_status_1](#)
- int [kappa_status_1](#)
- int [phi_status_1](#)
- int [dummy2](#)
- int [omega_status_2](#)
- int [alignx_status_2](#)
- int [aligny_status_2](#)
- int [alignz_status_2](#)
- int [analyzer_status_2](#)
- int [zoom_status_2](#)
- int [aperturey_status_2](#)
- int [aperturez_status_2](#)
- int [capy_status_2](#)
- int [capz_status_2](#)
- int [scint_status_2](#)
- int [centerx_status_2](#)
- int [centery_status_2](#)
- int [kappa_status_2](#)
- int [phi_status_2](#)
- int [dummy3](#)
- int [omega_act_pos](#)
- int [alignx_act_pos](#)
- int [aligny_act_pos](#)
- int [alignz_act_pos](#)
- int [analyzer_act_pos](#)
- int [zoom_act_pos](#)
- int [aperturey_act_pos](#)
- int [aperturez_act_pos](#)
- int [capy_act_pos](#)
- int [capz_act_pos](#)
- int [scint_act_pos](#)
- int [centerx_act_pos](#)
- int [centery_act_pos](#)
- int [kappa_act_pos](#)
- int [phi_act_pos](#)
- int [acc11c_1](#)
- int [acc11c_2](#)
- int [acc11c_3](#)
- int [acc11c_5](#)
- int [acc11c_6](#)
- int [front_dac](#)
- int [back_dac](#)
- int [scint_piezo](#)
- int [dummy4](#)
- int [dummy5](#)
- int [dummy6](#)
- int [dummy7](#)
- int [dummy8](#)
- int [dummy9](#)
- int [dummyA](#)
- int [dummyB](#)

- int [fs_is_open](#)
- int [phiscan](#)
- int [fs_has_opened](#)
- int [fs_has_opened_globally](#)
- int [number_passes](#)
- int [moving_flags](#)

4.16.1 Detailed Description

The block of memory retrieved in a status request.

Definition at line 203 of file `lspmac.c`.

4.16.2 Field Documentation

4.16.2.1 int md2StatusStruct::acc11c_1

Definition at line 270 of file `lspmac.c`.

4.16.2.2 int md2StatusStruct::acc11c_2

Definition at line 271 of file `lspmac.c`.

4.16.2.3 int md2StatusStruct::acc11c_3

Definition at line 272 of file `lspmac.c`.

4.16.2.4 int md2StatusStruct::acc11c_5

Definition at line 273 of file `lspmac.c`.

4.16.2.5 int md2StatusStruct::acc11c_6

Definition at line 274 of file `lspmac.c`.

4.16.2.6 int md2StatusStruct::alignx_act_pos

Definition at line 254 of file `lspmac.c`.

4.16.2.7 int md2StatusStruct::alignx_status_1

Definition at line 220 of file `lspmac.c`.

4.16.2.8 int md2StatusStruct::alignx_status_2

Definition at line 237 of file `lspmac.c`.

4.16.2.9 int md2StatusStruct::aligny_act_pos

Definition at line 255 of file `lspmac.c`.

4.16.2.10 int md2StatusStruct::aligny_status_1

Definition at line 221 of file lspmacc.c.

4.16.2.11 int md2StatusStruct::aligny_status_2

Definition at line 238 of file lspmacc.c.

4.16.2.12 int md2StatusStruct::alignz_act_pos

Definition at line 256 of file lspmacc.c.

4.16.2.13 int md2StatusStruct::alignz_status_1

Definition at line 222 of file lspmacc.c.

4.16.2.14 int md2StatusStruct::alignz_status_2

Definition at line 239 of file lspmacc.c.

4.16.2.15 int md2StatusStruct::analyzer_act_pos

Definition at line 257 of file lspmacc.c.

4.16.2.16 int md2StatusStruct::analyzer_status_1

Definition at line 223 of file lspmacc.c.

4.16.2.17 int md2StatusStruct::analyzer_status_2

Definition at line 240 of file lspmacc.c.

4.16.2.18 int md2StatusStruct::aperturey_act_pos

Definition at line 259 of file lspmacc.c.

4.16.2.19 int md2StatusStruct::aperturey_status_1

Definition at line 225 of file lspmacc.c.

4.16.2.20 int md2StatusStruct::aperturey_status_2

Definition at line 242 of file lspmacc.c.

4.16.2.21 int md2StatusStruct::aperturez_act_pos

Definition at line 260 of file lspmacc.c.

4.16.2.22 int md2StatusStruct::aperturez_status_1

Definition at line 226 of file lspmac.c.

4.16.2.23 int md2StatusStruct::aperturez_status_2

Definition at line 243 of file lspmac.c.

4.16.2.24 int md2StatusStruct::back_dac

Definition at line 276 of file lspmac.c.

4.16.2.25 int md2StatusStruct::capy_act_pos

Definition at line 261 of file lspmac.c.

4.16.2.26 int md2StatusStruct::capy_status_1

Definition at line 227 of file lspmac.c.

4.16.2.27 int md2StatusStruct::capy_status_2

Definition at line 244 of file lspmac.c.

4.16.2.28 int md2StatusStruct::capz_act_pos

Definition at line 262 of file lspmac.c.

4.16.2.29 int md2StatusStruct::capz_status_1

Definition at line 228 of file lspmac.c.

4.16.2.30 int md2StatusStruct::capz_status_2

Definition at line 245 of file lspmac.c.

4.16.2.31 int md2StatusStruct::centerx_act_pos

Definition at line 264 of file lspmac.c.

4.16.2.32 int md2StatusStruct::centerx_status_1

Definition at line 230 of file lspmac.c.

4.16.2.33 int md2StatusStruct::centerx_status_2

Definition at line 247 of file lspmac.c.

4.16.2.34 int md2StatusStruct::centery_act_pos

Definition at line 265 of file lspmacc.c.

4.16.2.35 int md2StatusStruct::centery_status_1

Definition at line 231 of file lspmacc.c.

4.16.2.36 int md2StatusStruct::centery_status_2

Definition at line 248 of file lspmacc.c.

4.16.2.37 int md2StatusStruct::dummy1

Definition at line 218 of file lspmacc.c.

4.16.2.38 int md2StatusStruct::dummy2

Definition at line 235 of file lspmacc.c.

4.16.2.39 int md2StatusStruct::dummy3

Definition at line 252 of file lspmacc.c.

4.16.2.40 int md2StatusStruct::dummy4

Definition at line 279 of file lspmacc.c.

4.16.2.41 int md2StatusStruct::dummy5

Definition at line 280 of file lspmacc.c.

4.16.2.42 int md2StatusStruct::dummy6

Definition at line 281 of file lspmacc.c.

4.16.2.43 int md2StatusStruct::dummy7

Definition at line 282 of file lspmacc.c.

4.16.2.44 int md2StatusStruct::dummy8

Definition at line 283 of file lspmacc.c.

4.16.2.45 int md2StatusStruct::dummy9

Definition at line 284 of file lspmacc.c.

4.16.2.46 int md2StatusStruct::dummyA

Definition at line 285 of file lspmac.c.

4.16.2.47 int md2StatusStruct::dummyB

Definition at line 286 of file lspmac.c.

4.16.2.48 int md2StatusStruct::front_dac

Definition at line 275 of file lspmac.c.

4.16.2.49 int md2StatusStruct::fs_has_opened

Definition at line 290 of file lspmac.c.

4.16.2.50 int md2StatusStruct::fs_has_opened_globally

Definition at line 291 of file lspmac.c.

4.16.2.51 int md2StatusStruct::fs_is_open

Definition at line 288 of file lspmac.c.

4.16.2.52 int md2StatusStruct::kappa_act_pos

Definition at line 266 of file lspmac.c.

4.16.2.53 int md2StatusStruct::kappa_status_1

Definition at line 232 of file lspmac.c.

4.16.2.54 int md2StatusStruct::kappa_status_2

Definition at line 249 of file lspmac.c.

4.16.2.55 int md2StatusStruct::moving_flags

Definition at line 294 of file lspmac.c.

4.16.2.56 int md2StatusStruct::number_passes

Definition at line 292 of file lspmac.c.

4.16.2.57 int md2StatusStruct::omega_act_pos

Definition at line 253 of file lspmac.c.

4.16.2.58 int md2StatusStruct::omega_status_1

Definition at line 219 of file lspmac.c.

4.16.2.59 int md2StatusStruct::omega_status_2

Definition at line 236 of file lspmac.c.

4.16.2.60 int md2StatusStruct::phi_act_pos

Definition at line 267 of file lspmac.c.

4.16.2.61 int md2StatusStruct::phi_status_1

Definition at line 233 of file lspmac.c.

4.16.2.62 int md2StatusStruct::phi_status_2

Definition at line 250 of file lspmac.c.

4.16.2.63 int md2StatusStruct::phiscan

Definition at line 289 of file lspmac.c.

4.16.2.64 int md2StatusStruct::scint_act_pos

Definition at line 263 of file lspmac.c.

4.16.2.65 int md2StatusStruct::scint_piezo

Definition at line 277 of file lspmac.c.

4.16.2.66 int md2StatusStruct::scint_status_1

Definition at line 229 of file lspmac.c.

4.16.2.67 int md2StatusStruct::scint_status_2

Definition at line 246 of file lspmac.c.

4.16.2.68 int md2StatusStruct::zoom_act_pos

Definition at line 258 of file lspmac.c.

4.16.2.69 int md2StatusStruct::zoom_status_1

Definition at line 224 of file lspmac.c.

4.16.2.70 int md2StatusStruct::zoom_status_2

Definition at line 241 of file lspmac.c.

The documentation for this struct was generated from the following file:

- [lspmac.c](#)

4.17 tagEthernetCmd Struct Reference

PMAC ethernet packet definition.

```
#include <pgpmac.h>
```

Data Fields

- unsigned char [RequestType](#)
VR_UPLOAD or VR_DOWNLOAD.
- unsigned char [Request](#)
The command to run (VR_PMAC_GETMEM, etc).
- unsigned short [wValue](#)
Command parameter 1.
- unsigned short [wIndex](#)
Command parameter 2.
- unsigned short [wLength](#)
Number of bytes in bData.
- unsigned char [bData](#) [1492]
The data buffer, if required.

4.17.1 Detailed Description

PMAC ethernet packet definition.

Taken directly from the Delta Tau documentation.

Definition at line 72 of file pgpmac.h.

4.17.2 Field Documentation

4.17.2.1 unsigned char tagEthernetCmd::bData[1492]

The data buffer, if required.

Definition at line 78 of file pgpmac.h.

4.17.2.2 unsigned char tagEthernetCmd::Request

The command to run (VR_PMAC_GETMEM, etc).

Definition at line 74 of file pgpmac.h.

4.17.2.3 unsigned char tagEthernetCmd::RequestType

VR_UPLOAD or VR_DOWNLOAD.

Definition at line 73 of file pgpmac.h.

4.17.2.4 unsigned short tagEthernetCmd::wIndex

Command parameter 2.

Definition at line 76 of file pgpmac.h.

4.17.2.5 unsigned short tagEthernetCmd::wLength

Number of bytes in bData.

Definition at line 77 of file pgpmac.h.

4.17.2.6 unsigned short tagEthernetCmd::wValue

Command parameter 1.

Definition at line 75 of file pgpmac.h.

The documentation for this struct was generated from the following file:

- [pgpmac.h](#)

Chapter 5

File Documentation

5.1 kvredis.c File Reference

```
#include <stdio.h>
#include <stdlib.h>
#include <hiredis/hiredis.h>
#include <hiredis/async.h>
#include <poll.h>
#include <postgresql/libpq-fe.h>
#include <string.h>
```

Data Structures

- struct [lspgQueryQueueStruct](#)

Store each query along with it's callback function.

Macros

- #define [LS_PG_QUERY_QUEUE_LENGTH](#) 512
- #define [LS_PG_QUERY_STRING_LENGTH](#) 512
- #define [LS_PG_STATE_INIT](#) -4
- #define [LS_PG_STATE_INIT_POLL](#) -3
- #define [LS_PG_STATE_RESET](#) -2
- #define [LS_PG_STATE_RESET_POLL](#) -1
- #define [LS_PG_STATE_IDLE](#) 1
- #define [LS_PG_STATE_SEND](#) 2
- #define [LS_PG_STATE_SEND_FLUSH](#) 3
- #define [LS_PG_STATE_RECV](#) 4

Typedefs

- typedef struct [lspgQueryQueueStruct](#) [lspg_query_queue_t](#)

Store each query along with it's callback function.

Functions

- void [redisDisconnectCB](#) (const redisAsyncContext *ac, int status)
- void [debugCB](#) (redisAsyncContext *ac, void *reply, void *privdata)
- void [addRead](#) (void *data)
- void [delRead](#) (void *data)
- void [addWrite](#) (void *data)
- void [delWrite](#) (void *data)
- void [cleanup](#) (void *data)
- void [lspg_allkvs_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
- PQnoticeProcessor [lspg_notice_processor](#) (void *arg, const char *msg)
- [lspg_query_queue_t](#) * [lspg_query_next](#) ()
Return the next item in the postgresql queue.
- void [lspg_query_reply_next](#) ()
Remove the oldest item in the queue.
- [lspg_query_queue_t](#) * [lspg_query_reply_peek](#) ()
Return the next item in the reply queue but don't pop it since we may need it more than once.
- void [lspg_query_push](#) (void(*cb)(lspg_query_queue_t *, PGresult *), char *fmt,...)
Place a query on the queue.
- void [lspg_receive](#) ()
Receive a result of a query.
- void [lspg_pg_connect](#) ()
Connect to the pg server.
- void [lspg_flush](#) ()
Flush psql output buffer (ie, send the query)
- void [lspg_next_state](#) ()
Implements our state machine Does not strictly only set the next state as it also calls some functions that, perhaps, alters the state mid-function.
- void [lspg_send_next_query](#) ()
send the next queued query to the DB server
- void [lspg_pg_service](#) (struct pollfd *evt)
I/O control to/from the postgresql server.
- void [fd_service](#) (struct pollfd *evt)
- [main](#) ()

Variables

- static redisAsyncContext * [subac](#)
- static redisAsyncContext * [cmdac](#)
- static int [ls_pg_state](#) = LS_PG_STATE_INIT
State of the lspg state machine.
- static struct timeval
[lspg_time_sent](#) [now](#)
used to ensure we do not inundate the db server with connection requests
- static int [kvseq](#) = 0
used to synchronize pg.kvs and redis
- static [lspg_query_queue_t](#) [lspg_query_queue](#) [LS_PG_QUERY_QUEUE_LENGTH]
Our query queue.
- static unsigned int [lspg_query_queue_on](#) = 0
Next position to add something to the queue.
- static unsigned int [lspg_query_queue_off](#) = 0
The last item still being used (on == off means nothing in queue)

- static unsigned int `lspg_query_queue_reply` = 0
The current item being digested.
- static PGconn * `q` = NULL
Database connector.
- static PostgresPollingStatusType `lspg_connectPoll_response`
Used to determine state while connecting.
- static PostgresPollingStatusType `lspg_resetPoll_response`
Used to determine state while reconnecting.
- static struct pollfd `lspgfd`
our poll info
- static struct pollfd `subfd`
poll info for redis subscribe channel
- static struct pollfd `cmdfd`
poll info for redis command channel

5.1.1 Macro Definition Documentation

5.1.1.1 `#define LS_PG_QUERY_QUEUE_LENGTH 512`

Definition at line 12 of file kvredis.c.

5.1.1.2 `#define LS_PG_QUERY_STRING_LENGTH 512`

Definition at line 13 of file kvredis.c.

5.1.1.3 `#define LS_PG_STATE_IDLE 1`

Definition at line 19 of file kvredis.c.

5.1.1.4 `#define LS_PG_STATE_INIT -4`

Definition at line 15 of file kvredis.c.

5.1.1.5 `#define LS_PG_STATE_INIT_POLL -3`

Definition at line 16 of file kvredis.c.

5.1.1.6 `#define LS_PG_STATE_RECV 4`

Definition at line 22 of file kvredis.c.

5.1.1.7 `#define LS_PG_STATE_RESET -2`

Definition at line 17 of file kvredis.c.

5.1.1.8 `#define LS_PG_STATE_RESET_POLL -1`

Definition at line 18 of file kvredis.c.

5.1.1.9 #define LS_PG_STATE_SEND 2

Definition at line 20 of file kvredis.c.

5.1.1.10 #define LS_PG_STATE_SEND_FLUSH 3

Definition at line 21 of file kvredis.c.

5.1.2 Typedef Documentation

5.1.2.1 typedef struct lspgQueryQueueStruct lspg_query_queue_t

Store each query along with it's callback function.

All calls are asynchronous

5.1.3 Function Documentation

5.1.3.1 void addRead (void * *data*)

Definition at line 111 of file kvredis.c.

```

    {
        struct pollfd *pfd;
        pfd = (struct pollfd *)data;
        pfd->events |= POLLIN;
    }

```

5.1.3.2 void addWrite (void * *data*)

Definition at line 121 of file kvredis.c.

```

    {
        struct pollfd *pfd;
        pfd = (struct pollfd *)data;
        pfd->events |= POLLOUT;
    }

```

5.1.3.3 void cleanup (void * *data*)

Definition at line 131 of file kvredis.c.

```

    {
        struct pollfd *pfd;
        pfd = (struct pollfd *)data;
        pfd->events &= ~(POLLOUT | POLLIN);
    }

```

5.1.3.4 void debugCB (redisAsyncContext * *ac*, void * *reply*, void * *privdata*)

Definition at line 63 of file kvredis.c.

```

    {
        static int indentlevel = 0;
        redisReply *r;
        int i;

```



```

r = (redisReply *)reply;

if( r == NULL) {
    printf( "Null reply.  Odd\n");
    return;
}

switch( r->type) {
case REDIS_REPLY_STATUS:
    printf( "%sSTATUS: %s\n", indentlevel*4, "", r->str);
    break;

case REDIS_REPLY_ERROR:
    printf( "%sERROR: %s\n", indentlevel*4, "", r->str);
    break;

case REDIS_REPLY_INTEGER:
    printf( "%sInteger: %lld\n", indentlevel*4, "", r->integer);
    break;

case REDIS_REPLY_NIL:
    printf( "%s(nil)\n", indentlevel*4, "");
    break;

case REDIS_REPLY_STRING:
    printf( "%sSTRING: %s\n", indentlevel*4, "", r->str);
    break;

case REDIS_REPLY_ARRAY:
    printf( "%sARRAY of %d elements\n", indentlevel*4, "", (int)r->elements);
    indentlevel++;
    for( i=0; i<r->elements; i++) {
        debugCB( ac, r->element[i], NULL);
    }
    indentlevel--;
    break;

default:
    printf( "%sUnknown type %d\n", indentlevel*4, "", r->type);
}
}
}

```

5.1.3.5 void delRead (void * data)

Definition at line 116 of file kvredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events &= ~POLLIN;
}

```

5.1.3.6 void delWrite (void * data)

Definition at line 126 of file kvredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events &= ~POLLOUT;
}

```

5.1.3.7 void fd_service (struct pollfd * evt)

Definition at line 636 of file kvredis.c.

```

{
    if( evt->fd == subac->c.fd) {
        if( evt->revents & POLLIN)
            redisAsyncHandleRead( subac);
        if( evt->revents & POLLOUT)

```

```

        redisAsyncHandleWrite( subac);
    }
    if( evt->fd == cmdac->c.fd) {
        if( evt->revents & POLLIN)
            redisAsyncHandleRead( cmdac);
        if( evt->revents & POLLOUT)
            redisAsyncHandleWrite( cmdac);
    }
    if( q && evt->fd == PQsocket( q))
        lspg_pg_service( evt);
}

```

5.1.3.8 void lspg_allkvs.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Definition at line 137 of file kvredis.c.

```

{
    int kvname_col, kvvalue_col, kvseq_col, kvdbrtype_col;
    int i;
    int seq;
    char *argv[8];

    kvname_col = PQfnumber( pgr, "rname");
    kvvalue_col = PQfnumber( pgr, "rvalue");
    kvseq_col = PQfnumber( pgr, "rseq");
    kvdbrtype_col = PQfnumber( pgr, "rdbrtype");

    if( kvname_col == -1 || kvvalue_col == -1 || kvseq_col == -1 || kvdbrtype_col
        == -1) {
        fprintf( stderr, "lspg_allkvs.cb: bad column number(s)\n");
        return;
    }

    redisAsyncCommand( cmdac, NULL, NULL, "MULTI");
    for( i=0; i<PQntuples( pgr); i++) {
        seq = atoi( PQgetvalue( pgr, i, kvseq_col));
        kvseq = kvseq < seq ? seq : kvseq;

        argv[0] = "HMSET";
        argv[1] = PQgetvalue( pgr, i, kvname_col);
        argv[2] = "VALUE";
        argv[3] = PQgetvalue( pgr, i, kvvalue_col);
        argv[4] = "SEQ";
        argv[5] = PQgetvalue( pgr, i, kvseq_col);
        argv[6] = "DBRTYPE";
        argv[7] = PQgetvalue( pgr, i, kvdbrtype_col);
        redisAsyncCommandArgv( cmdac, NULL, NULL, 8, (const char **)argv, NULL
            );

        argv[0] = "PUBLISH";
        argv[1] = "REDIS_KV_CONNECTOR";
        argv[2] = PQgetvalue( pgr, i, kvname_col);
        redisAsyncCommandArgv( cmdac, NULL, NULL, 3, (const char **)argv, NULL
            );
    }

    redisAsyncCommand( cmdac, NULL, NULL, "SET redis.kvseq %d", kvseq);

    redisAsyncCommand( cmdac, NULL, NULL, "EXEC");
}

```

5.1.3.9 void lspg_flush ()

Flush psql output buffer (ie, send the query)

Definition at line 412 of file kvredis.c.

```

{
    int err;

    err = PQflush( q);
    switch( err) {
    case -1:
        // an error occurred

        fprintf( stderr, "flush failed: %s\n", PQerrorMessage( q));
    }
}

```

```

    ls_pg_state = LS_PG_STATE_IDLE;
    //
    // We should probably reset the connection and start from scratch.
    // Probably the connection died.
    //
    break;

case 0:
    // goodness and joy.
    ls_pg_state = LS_PG_STATE_RECV;
    break;

case 1:
    // more sending to do
    ls_pg_state = LS_PG_STATE_SEND_FLUSH;
    break;
}
}
}

```

5.1.3.10 void lspg_next_state ()

Implements our state machine Does not strictly only set the next state as it also calls some functions that, perhaps, alters the state mid-function.

Definition at line 444 of file kvredis.c.

```

{
//
// connect to the database
//
if( q == NULL ||
    ls_pg_state == LS_PG_STATE_INIT ||
    ls_pg_state == LS_PG_STATE_RESET ||
    ls_pg_state == LS_PG_STATE_INIT_POLL ||
    ls_pg_state == LS_PG_STATE_RESET_POLL)
    lspg_pg_connect( lspgfd);

if( ls_pg_state == LS_PG_STATE_IDLE &&
    lspg_query_queue_on != lspg_query_queue_off
)
    ls_pg_state = LS_PG_STATE_SEND;

switch( ls_pg_state) {
case LS_PG_STATE_INIT_POLL:
    if( lspg_connectPoll_response ==
        PGRES_POLLING_WRITING)
        lspgfd.events = POLLOUT;
    else if( lspg_connectPoll_response ==
        PGRES_POLLING_READING)
        lspgfd.events = POLLIN;
    else
        lspgfd.events = 0;
    break;

case LS_PG_STATE_RESET_POLL:
    if( lspg_resetPoll_response == PGRES_POLLING_WRITING
    )
        lspgfd.events = POLLOUT;
    else if( lspg_resetPoll_response ==
        PGRES_POLLING_READING)
        lspgfd.events = POLLIN;
    else
        lspgfd.events = 0;
    break;

case LS_PG_STATE_IDLE:
case LS_PG_STATE_RECV:
    lspgfd.events = POLLIN;
    break;

case LS_PG_STATE_SEND:
case LS_PG_STATE_SEND_FLUSH:
    lspgfd.events = POLLOUT;
    break;

default:
    lspgfd.events = 0;
}
}

```

5.1.3.11 PQnoticeProcessor lspg_notice_processor (void * arg, const char * msg)

Definition at line 182 of file kvredis.c.

```

                                                                    {
    fprintf( stderr, "lspg: %s", msg);
}

```

5.1.3.12 void lspg_pg_connect ()

Connect to the pg server.

Definition at line 325 of file kvredis.c.

```

    {
    PGresult *pgr;
    int wait_interval = 1;
    int connection_init = 0;
    int i, err;

    if( q == NULL)
        ls_pg_state = LS_PG_STATE_INIT;

    switch( ls_pg_state) {
    case LS_PG_STATE_INIT:

        if( lspg_time_sent.tv_sec != 0) {
            //
            // Reality check: if it's less the about 10 seconds since the last failed
            // attempt
            // the just chill.
            //
            gettimeofday( &now, NULL);
            if( now.tv_sec - lspg_time_sent.tv_sec < 10) {
                return;
            }
        }

        q = PQconnectStart( "dbname=ls user=lsuser hostaddr=10.1.0.3");
        if( q == NULL) {
            fprintf( stderr, "Out of memory (lspg_pg_connect)");
            exit( -1);
        }

        err = PQstatus( q);
        if( err == CONNECTION_BAD) {
            fprintf( stderr, "Trouble connecting to database");

            gettimeofday( &lspg_time_sent, NULL);
            return;
        }
        err = PQsetnonblocking( q, 1);
        if( err != 0) {
            fprintf( stderr, "Odd, could not set database connection to nonblocking")
            ;
        }

        ls_pg_state = LS_PG_STATE_INIT_POLL;
        lspg_connectPoll_response = PGRES_POLLING_WRITING;
        //
        // set up the connection for poll
        //
        lspgfd.fd = PQsocket( q);
        break;

    case LS_PG_STATE_INIT_POLL:
        if( lspg_connectPoll_response ==
            PGRES_POLLING_FAILED) {
            PQfinish( q);
            q = NULL;
            ls_pg_state = LS_PG_STATE_INIT;
        } else if( lspg_connectPoll_response ==
            PGRES_POLLING_OK) {
            PQsetNoticeProcessor( q, (PQnoticeProcessor)lspg_notice_processor
            , NULL);

            ls_pg_state = LS_PG_STATE_IDLE;
        }
        break;
    }
}

```

```

case LS_PG_STATE_RESET:
    err = PQresetStart( q );
    if( err == 0 ) {
        PQfinish( q );
        q = NULL;
        ls_pg_state = LS_PG_STATE_INIT;
    } else {
        ls_pg_state = LS_PG_STATE_RESET_POLL;
        lspg_resetPoll_response = PGRES_POLLING_WRITING;
    }
    break;

case LS_PG_STATE_RESET_POLL:
    if( lspg_resetPoll_response == PGRES_POLLING_FAILED )
    {
        PQfinish( q );
        q = NULL;
        ls_pg_state = LS_PG_STATE_INIT;
    } else if( lspg_resetPoll_response ==
        PGRES_POLLING_OK ) {
        ls_pg_state = LS_PG_STATE_IDLE;
    }
    break;
}
}

```

5.1.3.13 void lspg_pg_service (struct pollfd * evt)

I/O control to/from the postgresql server.

Parameters

in	evt	The pollfd object that we are responding to
----	-----	---

Definition at line 543 of file kvredis.c.

```

{
//
// Currently just used to check for notifies
// Other socket communication is done synchronously
//

if( evt->revents & POLLIN ) {
    int err;

    if( ls_pg_state == LS_PG_STATE_INIT_POLL ) {
        lspg_connectPoll_response = PQconnectPoll( q );
        if( lspg_connectPoll_response ==
            PGRES_POLLING_FAILED ) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

    if( ls_pg_state == LS_PG_STATE_RESET_POLL )
    {
        lspg_resetPoll_response = PQresetPoll( q );
        if( lspg_resetPoll_response ==
            PGRES_POLLING_FAILED ) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

//
// if in IDLE or RECV we need to call consumeInput first
//
if( ls_pg_state == LS_PG_STATE_IDLE ) {
    err = PQconsumeInput( q );
    if( err != 1 ) {
        fprintf( stderr, "consume input failed: %s", PQerrorMessage( q ) );
        ls_pg_state == LS_PG_STATE_RESET;
        return;
    }
}

if( ls_pg_state == LS_PG_STATE_RECV ) {
    lspg_receive();
}
}

```

```

    }

    //
    // Check for notifies regardless of our state
    // Push as many requests as we have notifies.
    //
    {
        PGnotify *pgn;

        while( 1) {
            pgn = PQnotifies( q);
            if( pgn == NULL)
                break;

            lspg_query_push( lspg_allkvs_cb, "SELECT *
            FROM px.redis_kv_update(%d)", kvseq);

            PQfreemem( pgn);
        }
    }
}

if( evt->revents & POLLOUT) {

    if( ls_pg_state == LS_PG_STATE_INIT_POLL) {
        lspg_connectPoll_response = PQconnectPoll( q);
        if( lspg_connectPoll_response ==
        PGRES_POLLING_FAILED) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

    if( ls_pg_state == LS_PG_STATE_RESET_POLL)
    {
        lspg_resetPoll_response = PQresetPoll( q);
        if( lspg_resetPoll_response ==
        PGRES_POLLING_FAILED) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

    if( ls_pg_state == LS_PG_STATE_SEND) {
        lspg_send_next_query();
    }

    if( ls_pg_state == LS_PG_STATE_SEND_FLUSH)
    {
        lspg_flush();
    }
}
}
}

```

5.1.3.14 lspg_query_queue_t* lspg_query_next()

Return the next item in the postgresql queue.

If there is an item left in the queue then it is returned. Otherwise, NULL is returned.

Definition at line 191 of file kvredis.c.

```

{
    lspg_query_queue_t *rtn;

    if( lspg_query_queue_off == lspg_query_queue_on
    )
        // Queue is empty
        rtn = NULL;
    else {
        rtn = &(lspg_query_queue[ (lspg_query_queue_off
        ++)% LS_PG_QUERY_QUEUE_LENGTH]);
    }
    return rtn;
}

```

5.1.3.15 void lspg_query_push (void(*) (lspg_query_queue_t *, PGresult *) cb, char * fmt, ...)

Place a query on the queue.

Parameters

in	<i>cb</i>	Our callback function that deals with the response
in	<i>fmt</i>	Printf style function to generate the query

Definition at line 234 of file kvredis.c.

```

{
    int idx;
    va_list arg_ptr;

    //
    // Pause the thread while we service the queue
    //
    if( lspg_query_queue_on + 1 == lspg_query_queue_off
    ) {
        fprintf( stderr, "lspg_query_push: queue is full. Ignoring query \"%s\"\n"
            , fmt);
        return;
    }

    idx = lspg_query_queue_on % LS_PG_QUERY_QUEUE_LENGTH
        ;

    va_start( arg_ptr, fmt);
    vsnprintf( lspg_query_queue[idx].qs,
        LS_PG_QUERY_STRING_LENGTH-1, fmt, arg_ptr);
    va_end( arg_ptr);

    lspg_query_queue[idx].qs[LS_PG_QUERY_STRING_LENGTH
        - 1] = 0;
    lspg_query_queue[idx].onResponse = cb;
    lspg_query_queue_on++;
};

```

5.1.3.16 void lspg_query_reply_next ()

Remove the oldest item in the queue.

this is called only when there is nothing else to service the reply: this pop does not return anything. We use the ...reply_peek function to return the next item in the reply queue

Definition at line 211 of file kvredis.c.

```

{
    if( lspg_query_queue_reply != lspg_query_queue_on
    )
        lspg_query_queue_reply++;
}

```

5.1.3.17 lspg_query_queue_t* lspg_query_reply_peek ()

Return the next item in the reply queue but don't pop it since we may need it more than once.

Call `lspg_query_reply_next()` when done.

Definition at line 221 of file kvredis.c.

```

{
    lspg_query_queue_t *rtn;

    if( lspg_query_queue_reply == lspg_query_queue_on

```

```

    )
    rtn = NULL;
else
    rtn = &(lspg_query_queue[ (lspg_query_queue_reply
    ) % LS_PG_QUERY_QUEUE_LENGTH]);
return rtn;
}

```

5.1.3.18 void lspg_receive ()

Receive a result of a query.

Definition at line 266 of file kvredis.c.

```

{
PGresult *pgr;
lspg_query_queue_t *qqp;
int err;

err = PQconsumeInput( q);
if( err != 1) {
    fprintf( stderr, "consume input failed: %s", PQerrorMessage( q));
    ls_pg_state == LS_PG_STATE_RESET;
    return;
}

//
// We must call PQgetResult until it returns NULL before sending the next
// query
// This implies that only one query can ever be active at a time and our
// queue
// management should be simple
//
// We should be in the LS_PG_STATE_RECV here
//

while( !PQisBusy( q)) {
    pgr = PQgetResult( q);
    if( pgr == NULL) {
        lspg_query_reply_next();
        //
        // we are now done reading the response from the database
        //
        ls_pg_state = LS_PG_STATE_IDLE;
        break;
    } else {
        ExecStatusType es;

        qqp = lspg_query_reply_peek();
        es = PQresultStatus( pgr);

        if( es != PGRES_COMMAND_OK && es != PGRES_TUPLES_OK) {
            char *emess;
            emess = PQresultErrorMessage( pgr);
            if( emess != NULL && emess[0] != 0) {
                fprintf( stderr, "Error from query '%s':\n%s", qqp->q, emess);
            }
        } else {
            //
            // Deal with the response
            //
            // If the response is likely to take awhile we should probably
            // add a new state and put something in the main loop to run the
            onResponse
            // routine in the main loop. For now, though, we only expect very
            brief onResponse routines
            //
            if( qqp != NULL && qqp->onResponse != NULL)
                qqp->onResponse( qqp, pgr);
        }
        PQclear( pgr);
    }
}
}

```

5.1.3.19 void lspg_send_next_query ()

send the next queued query to the DB server

Definition at line 496 of file kvredis.c.

```

    {
//
// Normally we should be in the "send" state
// but we can also send if we are servicing
// a reply
//

lspg_query_queue_t *qqp;
int err;

qqp = lspg_query_next();
if( qqp == NULL) {
//
// A send without a query? Should never happen.
// But at least we shouldn't segfault if it does.
//
return;
}

if( qqp->qs[0] == 0) {
//
// Do we really have to check this case?
// It would only come up if we stupidly pushed an empty query string
// or ran off the end of the queue
//
fprintf( stderr, "Popped empty query string. Probably bad things are going
on.\n");

lspg_query_reply_next();
ls_pg_state = LS_PG_STATE_IDLE;
} else {
err = PQsendQuery( q, qqp->qs);
if( err == 0) {
fprintf( stderr, "query failed: %s\n", PQerrorMessage( q));

//
// Don't wait for a reply, just reset the connection
//
lspg_query_reply_next();
ls_pg_state == LS_PG_STATE_RESET;
} else {
ls_pg_state = LS_PG_STATE_SEND_FLUSH;
}
}
}
}

```

5.1.3.20 main()

Definition at line 655 of file kvredis.c.

```

{
static struct pollfd fda[3];
static int nfda = 0;
int pollrtn;
int poll_timeout_ms;
int i;

subac = redisAsyncConnect("127.0.0.1", 6379);
if( subac->err) {
fprintf( stderr, "Error: %s\n", subac->errstr);
exit( -1);
}

cmdac = redisAsyncConnect("127.0.0.1", 6379);
if( cmdac->err) {
fprintf( stderr, "Error: %s\n", cmdac->errstr);
exit( -1);
}

if( redisAsyncSetDisconnectCallback( subac, redisDisconnectCB
) == REDIS_ERR) {
fprintf( stderr, "Error: could not set disconnect callback\n");
exit( -1);
}

if( redisAsyncSetDisconnectCallback( cmdac, redisDisconnectCB
) == REDIS_ERR) {
fprintf( stderr, "Error: could not set disconnect callback\n");
exit( -1);
}
}

```

```

}

// Set up redis events
//
subfd.fd      = subac->c.fd;
subfd.events  = 0;
subac->ev.data  = &subfd;
subac->ev.addRead  = addRead;
subac->ev.delRead  = delRead;
subac->ev.addWrite = addWrite;
subac->ev.delWrite = delWrite;
subac->ev.cleanup  = cleanup;

cmdfd.fd      = cmdac->c.fd;
cmdfd.events  = 0;
cmdac->ev.data  = &cmdfd;
cmdac->ev.addRead  = addRead;
cmdac->ev.delRead  = delRead;
cmdac->ev.addWrite = addWrite;
cmdac->ev.delWrite = delWrite;
cmdac->ev.cleanup  = cleanup;

lspgfd.fd = -1;

if( redisAsyncCommand( cmdac, NULL, NULL, "KEYS *" ) == REDIS_ERR ) {
    fprintf( stderr, "Error sending KEYS command\n");
    exit( -1);
}

if( redisAsyncCommand( subac, debugCB, NULL, "PSUBSCRIBE MD2* UI*" ) == REDIS_ERR ) {
    fprintf( stderr, "Error sending PSUBSCRIBE command\n");
    exit( -1);
}

lspg_query_push( lspg_allkvs_cb, "SELECT * FROM
    px.redis_kv_init()" );
lspg_query_push( NULL, "LISTEN REDIS_KV_CONNECTOR");

while( 1 ) {
    nfda = 0;
    if( subfd.fd != -1 ) {
        fda[nfda].fd      = subfd.fd;
        fda[nfda].events  = subfd.events;
        fda[nfda].revents = 0;

        nfda++;
    }
    if( cmdfd.fd != -1 ) {
        fda[nfda].fd      = cmdfd.fd;
        fda[nfda].events  = cmdfd.events;
        fda[nfda].revents = 0;

        nfda++;
    }
    poll_timeout_ms = -1;

    lspg_next_state();

    if( lspgfd.fd == -1 ) {
        //
        // Here a connection to the database is not established.
        // Periodicaly try again. Should possibly arrange to reconnect
        // to signalfd but that's unlikely to be necessary.
        //
        poll_timeout_ms = 10000;
    } else {
        //
        // Arrange to peacefully do nothing until either the pg server sends us
        // something
        // or someone pushes something onto our queue
        //
        fda[nfda].fd      = lspgfd.fd;
        fda[nfda].events  = lspgfd.events;
        fda[nfda].revents = 0;
        nfda++;
        poll_timeout_ms = -1;
    }
}

pollrtn = poll( fda, nfda, poll_timeout_ms);

for( i=0; i<nfda; i++) {
    if( fda[i].revents ) {
        fd_service( &(fda[i]));
    }
}

```

```

    }
}
}

```

5.1.3.21 void redisDisconnectCB (const redisAsyncContext * ac, int status)

Definition at line 54 of file kvredis.c.

```

{
    if( status == REDIS_OK) {
        printf( "OK, that was fun.\n");
        exit( 0);
    }
    fprintf( stderr, "Oops, Disconnected with status %d\n", status);
    exit( -1);
}

```

5.1.4 Variable Documentation

5.1.4.1 redisAsyncContext * cmdac [static]

Definition at line 9 of file kvredis.c.

5.1.4.2 struct pollfd cmdfd [static]

poll info for redis command channel

Definition at line 50 of file kvredis.c.

5.1.4.3 int kvseq = 0 [static]

used to synchronize pg.kvs and redis

Definition at line 26 of file kvredis.c.

5.1.4.4 int ls_pg_state = LS_PG_STATE_INIT [static]

State of the lspg state machine.

Definition at line 24 of file kvredis.c.

5.1.4.5 PostgresPollingStatusType lspg_connectPoll_response [static]

Used to determine state while connecting.

Definition at line 46 of file kvredis.c.

5.1.4.6 lspg_query_queue_t lspg_query_queue[LS_PG_QUERY_QUEUE_LENGTH] [static]

Our query queue.

Definition at line 37 of file kvredis.c.

5.1.4.7 unsigned int lspg_query_queue_off = 0 [static]

The last item still being used (on == off means nothing in queue)

Definition at line 39 of file kvredis.c.

5.1.4.8 `unsigned int lspg_query_queue_on = 0` `[static]`

Next position to add something to the queue.

Definition at line 38 of file kvredis.c.

5.1.4.9 `unsigned int lspg_query_queue_reply = 0` `[static]`

The current item being digested.

Normally off <= reply <= on. Corner case of queue wrap around works because we only increment and compare for equality.

Definition at line 40 of file kvredis.c.

5.1.4.10 `PostgresPollingStatusType lspg_resetPoll_response` `[static]`

Used to determine state while reconnecting.

Definition at line 47 of file kvredis.c.

5.1.4.11 `struct pollfd lspgfd` `[static]`

our poll info

Definition at line 48 of file kvredis.c.

5.1.4.12 `struct timeval lspg_time_sent now` `[static]`

used to ensure we do not inundate the db server with connection requests

Definition at line 25 of file kvredis.c.

5.1.4.13 `PGconn* q = NULL` `[static]`

Database connector.

Definition at line 45 of file kvredis.c.

5.1.4.14 `redisAsyncContext* subac` `[static]`

Definition at line 9 of file kvredis.c.

5.1.4.15 `struct pollfd subfd` `[static]`

poll info for redis subscribe channel

Definition at line 49 of file kvredis.c.

5.2 Isevents.c File Reference

event subsystem for inter-pgpmac communication

```
#include "pgpmac.h"
```

Data Structures

- struct [lsevents_queue_struct](#)
Storage definition for the events.
- struct [lsevents_listener_struct](#)
Linked list of event listeners.

Macros

- #define [LSEVENTS_QUEUE_LENGTH](#) 2096

Typedefs

- typedef struct
[lsevents_queue_struct](#) [lsevents_queue_t](#)
Storage definition for the events.
- typedef struct
[lsevents_listener_struct](#) [lsevents_listener_t](#)
Linked list of event listeners.

Functions

- void [lsevents_send_event](#) (char *fmt,...)
Call the callback routines for the given event.
- void [lsevents_add_listener](#) (char *event, void(*cb)(char *))
Add a callback routine to listen for a specific event.
- void [lsevents_remove_listener](#) (char *event, void(*cb)(char *))
Remove a listener previously added with lsevents_add_listener.
- void * [lsevents_worker](#) (void *dummy)
Our worker.
- void [lsevents_init](#) ()
Initialize this module.
- void [lsevents_run](#) ()
Start up the thread and get out of the way.

Variables

- static [lsevents_queue_t](#) [lsevents_queue](#) [[LSEVENTS_QUEUE_LENGTH](#)]
simple list of events
- static unsigned int [lsevents_queue_on](#) = 0
next queue location to write
- static unsigned int [lsevents_queue_off](#) = 0
next queue location to read
- static [lsevents_listener_t](#) * [lsevents_listeners_p](#) = NULL
Pointer to the first item in the link list of listeners.
- static pthread_t [lsevents_thread](#)
thread to run the event queue
- static pthread_mutex_t [lsevents_listener_mutex](#)
mutex to protect the listener linked list
- static pthread_mutex_t [lsevents_queue_mutex](#)
mutex to protect the event queue
- static pthread_cond_t [lsevents_queue_cond](#)
condition to pause the queue if needed

5.2.1 Detailed Description

event subsystem for inter-pgpmac communication

Date

2012

Author

Keith Brister

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Definition in file [lsevents.c](#).

5.2.2 Macro Definition Documentation

5.2.2.1 `#define LSEVENTS_QUEUE_LENGTH 2096`

Definition at line 10 of file lsevents.c.

5.2.3 Typedef Documentation

5.2.3.1 `typedef struct lsevents_listener_struct lsevents_listener_t`

Linked list of event listeners.

5.2.3.2 `typedef struct lsevents_queue_struct lsevents_queue_t`

Storage definition for the events.

Just a string for now. Perhaps one day we'll succumb to the temptation to add an argument or two.

5.2.4 Function Documentation

5.2.4.1 `void lsevents_add_listener (char * event, void(*)(char *) cb)`

Add a callback routine to listen for a specific event.

Parameters

<i>event</i>	the name of the event to listen for
<i>cb</i>	the routine to call

Definition at line 78 of file lsevents.c.

```

lsevents_listener_t *new;
int err;
char *errbuf;
int nerrbuf;
{

```

```

new = calloc( 1, sizeof( lsevents_listener_t));
if( new == NULL) {
    lslogging_log_message( "lsevents_add_listener: out of
        memory");
    exit( -1);
}

err = regcomp( &new->re, event, REG_EXTENDED | REG_NOSUB);
if( err != 0) {
    nerrbuf = regerror( err, &new->re, NULL, 0);
    errbuf = calloc( nerrbuf, sizeof( char));
    if( errbuf == NULL) {
        lslogging_log_message( "lsevents_add_listener: out
            of memory (re)");
        exit( -1);
    }
    regerror( err, &new->re, errbuf, nerrbuf);
    lslogging_log_message( "lsevents_add_listener: %s",
        errbuf);
    free( errbuf);
    free( new);
    return;
}

new->raw_regexp = strdup( event);
new->cb = cb;

pthread_mutex_lock( &lsevents_listener_mutex);
new->next = lsevents_listeners_p;
lsevents_listeners_p = new;
pthread_mutex_unlock( &lsevents_listener_mutex);

lslogging_log_message( "lsevents_add_listener: added
    listener for event %s", event);
}

```

5.2.4.2 void lsevents_init()

Initialize this module.

Definition at line 207 of file lsevents.c.

```

{
    pthread_mutex_init( &lsevents_queue_mutex, NULL);
    pthread_cond_init( &lsevents_queue_cond, NULL);
    pthread_mutex_init( &lsevents_listener_mutex, NULL);
}

```

5.2.4.3 void lsevents_remove_listener(char * event, void (*)(char *) cb)

Remove a listener previously added with lsevents_add_listener.

Parameters

<i>event</i>	The name of the event
<i>cb</i>	The callback routine to remove

Definition at line 123 of file lsevents.c.

```

{

lsevents_listener_t *last, *current;

//
// Find the listener to remove
// and unlink it from the list
//
pthread_mutex_lock( &lsevents_listener_mutex);
last = NULL;
for( current = lsevents_listeners_p; current != NULL;
    current = current->next) {
    if( strcmp( last->raw_regexp, event) == 0 && last->cb == cb) {

```

```

    if( last == NULL) {
        lsevents_listeners_p = current->next;
    } else {
        last->next = current->next;
    }
    break;
}
}
pthread_mutex_unlock( &lsevents_listener_mutex);

//
// Now remove it
//
if( current != NULL) {
    if( current->raw_regexp != NULL)
        free( current->raw_regexp);
    free(current);
}
}
}

```

5.2.4.4 void lsevents_run ()

Start up the thread and get out of the way.

Definition at line 215 of file lsevents.c.

```

{
    pthread_create( &lsevents_thread, NULL, lsevents_worker
, NULL);
}

```

5.2.4.5 void lsevents_send_event (char *fmt, ...)

Call the callback routines for the given event.

Parameters

<i>fmt</i>	a printf style formatting string
...	list of arguments specified by the format string

Definition at line 45 of file lsevents.c.

```

{
    char event[LSEVENTS_EVENT_LENGTH];
    char *sp;
    va_list arg_ptr;

    va_start( arg_ptr, fmt);
    vsnprintf( event, sizeof(event)-1, fmt, arg_ptr);
    event[sizeof(event)-1]=0;
    va_end( arg_ptr);

    pthread_mutex_lock( &lsevents_queue_mutex);

    lslogging_log_message( "lsevents_send_event: %s", event)
;

    // maybe wait for room on the queue
    while( lsevents_queue_on + 1 == lsevents_queue_off
)
        pthread_cond_wait( &lsevents_queue_cond, &
lsevents_queue_mutex);

    sp = lsevents_queue[(lsevents_queue_on++) %
LSEVENTS_QUEUE_LENGTH].event;
    strncpy( sp, event, LSEVENTS_EVENT_LENGTH);
    sp[LSEVENTS_EVENT_LENGTH - 1] = 0;

    pthread_cond_signal( &lsevents_queue_cond);
    pthread_mutex_unlock( &lsevents_queue_mutex);
}

```


5.2.4.6 void* lsevents_worker (void * dummy)

Our worker.

Parameters

<i>dummy</i>	Unused but needed by pthreads to be happy
--------------	---

Definition at line 158 of file lsevents.c.

```

    {
        char *event;
        lsevents_queue_t *ep;
        lsevents_listener_t *p;

        while( 1 ) {
            pthread_mutex_lock( &lsevents_queue_mutex);

            //
            // wait for someone to send an event
            //
            while( lsevents_queue_off == lsevents_queue_on
                )
                pthread_cond_wait( &lsevents_queue_cond, &
                    lsevents_queue_mutex);

            //
            // copy event string since the value in the queue may change when
            // we unlock the mutex
            //
            ep = &(lsevents_queue[(lsevents_queue_off++
                ) % LSEVENTS_QUEUE_LENGTH]);
            event = strdup( ep->event, LSEVENTS_EVENT_LENGTH
                -1);
            event[LSEVENTS_EVENT_LENGTH-1] = 0;

            //
            // let the send event process know there is room on the queue again
            //
            pthread_cond_signal( &lsevents_queue_cond);
            pthread_mutex_unlock( &lsevents_queue_mutex);

            //
            // Find the callbacks and, well, call them back
            //
            pthread_mutex_lock( &lsevents_listener_mutex);
            for( p = lsevents_listeners_p; p != NULL; p = p->next
                ) {
                if( regexec( &p->re, event, 0, NULL, 0) == 0 ) {
                    p->cb( event);
                }
            }
            free( event);

            pthread_mutex_unlock( &lsevents_listener_mutex);
        }
        return NULL;
    }

```

5.2.5 Variable Documentation

5.2.5.1 pthread_mutex_t lsevents_listener_mutex [static]

mutex to protect the listener linked list

Definition at line 37 of file lsevents.c.

5.2.5.2 lsevents_listener_t* lsevents.listeners_p = NULL [static]

Pointer to the first item in the link list of listeners.

Definition at line 34 of file lsevents.c.

5.2.5.3 `lsevents_queue_t lsevents_queue[LSEVENTS_QUEUE_LENGTH]` `[static]`

simple list of events

Definition at line 21 of file `lsevents.c`.

5.2.5.4 `pthread_cond_t lsevents_queue_cond` `[static]`

condition to pause the queue if needed

Definition at line 39 of file `lsevents.c`.

5.2.5.5 `pthread_mutex_t lsevents_queue_mutex` `[static]`

mutex to protect the event queue

Definition at line 38 of file `lsevents.c`.

5.2.5.6 `unsigned int lsevents_queue_off = 0` `[static]`

next queue location to read

Definition at line 23 of file `lsevents.c`.

5.2.5.7 `unsigned int lsevents_queue_on = 0` `[static]`

next queue location to write

Definition at line 22 of file `lsevents.c`.

5.2.5.8 `pthread_t lsevents_thread` `[static]`

thread to run the event queue

Definition at line 36 of file `lsevents.c`.

5.3 `lslogging.c` File Reference

Logs messages to a file.

```
#include "pgpmac.h"
```

Data Structures

- struct [lslogging_queue_struct](#)
Our log object: time and message.

Macros

- #define [LSLOGGING_FILE_NAME](#) `"/tmp/pgpmac.log"`
Full name of the log file.
- #define [LSLOGGING_MSG_LENGTH](#) `2048`
Fixed maximum length messages to keep some form of sanity.

- `#define LSLOGGING_QUEUE_LENGTH 8192`
Modest length queue.

Typedefs

- `typedef struct lslogging_queue_struct lslogging_queue_t`
Our log object: time and message.

Functions

- `void lslogging_init ()`
Initialize the lslogging objects.
- `void lslogging_log_message (char *fmt,...)`
The routine everyone will be talking about.
- `void * lslogging_worker (void *dummy)`
Service the queue, write to the file.
- `void lslogging_run ()`
Start up the worker thread.

Variables

- `static pthread_t lslogging_thread`
our thread
- `static pthread_mutex_t lslogging_mutex`
mutex to keep the various threads from adding to the queue at the exact same time
- `static pthread_cond_t lslogging_cond`
We'll spend most of our time waiting for this condition's signal.
- `static FILE * lslogging_file`
our log file object
- `static lslogging_queue_t lslogging_queue [LSLOGGING_QUEUE_LENGTH]`
Our entire queue. Right here. Every message we'll ever write.
- `static unsigned int lslogging_on = 0`
next location to add to the queue
- `static unsigned int lslogging_off = 0`
next location to remove from the queue

5.3.1 Detailed Description

Logs messages to a file.

Date

2012

Author

Keith Brister

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Definition in file [lslogging.c](#).

5.3.2 Macro Definition Documentation

5.3.2.1 `#define LSLOGGING_FILE_NAME "/tmp/pgpmac.log"`

Full name of the log file.

Probably should be in `/var/log/pgpmac`.

Definition at line 16 of file `lslogging.c`.

5.3.2.2 `#define LSLOGGING_MSG_LENGTH 2048`

Fixed maximum length messages to keep some form of sanity.

Definition at line 20 of file `lslogging.c`.

5.3.2.3 `#define LSLOGGING_QUEUE_LENGTH 8192`

Modest length queue.

Definition at line 30 of file `lslogging.c`.

5.3.3 Typedef Documentation

5.3.3.1 `typedef struct lslogging_queue_struct lslogging_queue_t`

Our log object: time and message.

5.3.4 Function Documentation

5.3.4.1 `void lslogging_init ()`

Initialize the `lslogging` objects.

Definition at line 37 of file `lslogging.c`.

```

{
    pthread_mutex_init( &lslogging_mutex, NULL);
    pthread_cond_init( &lslogging_cond, NULL);

    lslogging_file = fopen( LSLOGGING_FILE_NAME,
        "w");
}
```

5.3.4.2 `void lslogging_log_message (char * fmt, ...)`

The routine everyone will be talking about.

Parameters

<i>fmt</i>	A printf style formatting string.
...	The arguments specified by <i>fmt</i>

Definition at line 48 of file `lslogging.c`.

```

{
    char msg[LSLOGGING_MSG_LENGTH];
    struct timespec theTime;
    va_list arg_ptr;
```

```

unsigned int on;

clock_gettime( CLOCK_REALTIME, &theTime);

va_start( arg_ptr, fmt);
vsprintf( msg, sizeof(msg)-1, fmt, arg_ptr);
va_end( arg_ptr);
msg[sizeof(msg)-1]=0;

pthread_mutex_lock( &lslogging_mutex);

on = (lslogging_on++) % LSLOGGING_QUEUE_LENGTH
;
strncpy( lslogging_queue[on].lmsg, msg, LSLOGGING_MSG_LENGTH
- 1);
lslogging_queue[on].lmsg[LSLOGGING_MSG_LENGTH
-1] = 0;

memcpy( &(lslogging_queue[on].ltime), &theTime, sizeof(theTime
));

pthread_cond_signal( &lslogging_cond);
pthread_mutex_unlock( &lslogging_mutex);
}

```

5.3.4.3 void lslogging_run ()

Start up the worker thread.

Definition at line 105 of file lslogging.c.

```

{
pthread_create( &lslogging_thread, NULL, &lslogging_worker
, NULL);
lslogging_log_message( "Start up");
}

```

5.3.4.4 void* lslogging_worker (void * dummy)

Service the queue, write to the file.

Parameters

in	<i>dummy</i>	Required by protocol but unused
----	--------------	---------------------------------

Definition at line 76 of file lslogging.c.

```

{

struct tm coarsetime;
char tstr[64];
unsigned int msecs;
unsigned int off;

pthread_mutex_lock( &lslogging_mutex);

while( 1) {
while( lslogging_on == lslogging_off) {
pthread_cond_wait( &lslogging_cond, &lslogging_mutex
);
}

off = (lslogging_off++) % LSLOGGING_QUEUE_LENGTH
;
localtime_r( &(lslogging_queue[off].ltime.tv_sec), &
coarsetime);
strftime( tstr, sizeof(tstr)-1, "%Y-%m-%d %H:%M:%S", &coarsetime);
tstr[sizeof(tstr)-1] = 0;
msecs = lslogging_queue[off].ltime.tv_nsec / 1000;
fprintf( lslogging_file, "%s.%.06u %s\n", tstr, msecs,
lslogging_queue[off].lmsg);
fflush( lslogging_file);
}
}

```

```
}
}
```

5.3.5 Variable Documentation

5.3.5.1 `pthread_cond_t lslogging_cond` [static]

We'll spend most of our time waiting for this condition's signal.

Definition at line 12 of file `lslogging.c`.

5.3.5.2 `FILE* lslogging_file` [static]

our log file object

Definition at line 17 of file `lslogging.c`.

5.3.5.3 `pthread_mutex_t lslogging_mutex` [static]

mutex to keep the various threads from adding to the queue at the exact same time

Definition at line 11 of file `lslogging.c`.

5.3.5.4 `unsigned int lslogging_off = 0` [static]

next location to remove from the queue

Definition at line 34 of file `lslogging.c`.

5.3.5.5 `unsigned int lslogging_on = 0` [static]

next location to add to the queue

Definition at line 33 of file `lslogging.c`.

5.3.5.6 `lslogging_queue_t lslogging_queue[LSLOGGING_QUEUE_LENGTH]` [static]

Our entire queue. Right here. Every message we'll ever write.

Definition at line 31 of file `lslogging.c`.

5.3.5.7 `pthread_t lslogging_thread` [static]

our thread

Definition at line 10 of file `lslogging.c`.

5.4 lspg.c File Reference

Postgresql support for the LS-CAT pgpmac project.

```
#include "pgpmac.h"
```

Data Structures

- struct [lspgQueryQueueStruct](#)
Store each query along with it's callback function.
- struct [lspg_wait_for_detector_struct](#)
Object that implements detector / spindle timing We use database locks for exposure control and this implements the md2 portion of this handshake.
- struct [lspg_lock_diffractionmeter_struct](#)
Object used to impliment locking the diffractometer Critical to exposure timing.
- struct [lspg_lock_detector_struct](#)
lock detector object Implements detector lock for exposure control
- struct [lspg_seq_run_prep_struct](#)
Data collection running object.

Macros

- #define [LS_PG_STATE_INIT](#) -4
- #define [LS_PG_STATE_INIT_POLL](#) -3
- #define [LS_PG_STATE_RESET](#) -2
- #define [LS_PG_STATE_RESET_POLL](#) -1
- #define [LS_PG_STATE_IDLE](#) 1
- #define [LS_PG_STATE_SEND](#) 2
- #define [LS_PG_STATE_SEND_FLUSH](#) 3
- #define [LS_PG_STATE_RECV](#) 4
- #define [LS_PG_QUERY_QUEUE_LENGTH](#) 16384
Queue length should be long enough that we do not ordinarily bump into the end We should be safe as long as the thread the adds stuff to the queue is not the one that removes it.

Typedefs

- typedef struct [lspgQueryQueueStruct](#) [lspg_query_queue_t](#)
Store each query along with it's callback function.
- typedef struct [lspg_wait_for_detector_struct](#) [lspg_wait_for_detector_t](#)
Object that implements detector / spindle timing We use database locks for exposure control and this implements the md2 portion of this handshake.
- typedef struct [lspg_lock_diffractionmeter_struct](#) [lspg_lock_diffractionmeter_t](#)
Object used to impliment locking the diffractometer Critical to exposure timing.
- typedef struct [lspg_lock_detector_struct](#) [lspg_lock_detector_t](#)
lock detector object Implements detector lock for exposure control
- typedef struct [lspg_seq_run_prep_struct](#) [lspg_seq_run_prep_t](#)
Data collection running object.

Functions

- `lspg_query_queue_t * lspg_query_next ()`
Return the next item in the postgresql queue.
- `void lspg_query_reply_next ()`
Remove the oldest item in the queue.
- `lspg_query_queue_t * lspg_query_reply_peek ()`
Return the next item in the reply queue but don't pop it since we may need it more than once.
- `void lspg_query_push (void(*cb)(lspg_query_queue_t *, PGresult *), char *fmt,...)`
Place a query on the queue.
- `char ** lspg_array2ptrs (char *a)`
returns a null terminated list of strings parsed from postgresql array
- `void lspg_init_motors_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Motor initialization callback.
- `void lspg_zoom_lut_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Zoom motor look up table callback.
- `void lspg_scint_lut_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
- `void lspg_flight_lut_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Front Light Lookup table query callback Install the lookup table for the Front Light.
- `void lspg_blight_lut_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Back Light Lookup Table Callback Install the lookup table for the Back Light.
- `void lspg_nextshot_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Next Shot Callback.
- `void lspg_nextshot_init ()`
Initialize the nextshot variable, mutex, and condition.
- `void lspg_nextshot_call ()`
Queue up a nextshot query.
- `void lspg_nextshot_wait ()`
Wait for the next shot query to get processed.
- `void lspg_nextshot_done ()`
Called when the next shot query has been processed.
- `void lspg_wait_for_detector_init ()`
initialize the detector timing object
- `void lspg_wait_for_detector_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Callback for the wait for detector query.
- `void lspg_wait_for_detector_call ()`
initiate the wait for detector query
- `void lspg_wait_for_detector_wait ()`
Pause the calling thread until the detector is ready Called by the MD2 thread.
- `void lspg_wait_for_detector_done ()`
Done waiting for the detector.
- `void lspg_wait_for_detector_all ()`
Combined call to wait for the detector.
- `void lspg_lock_diffractionmeter_init ()`
initialize the diffractionmeter locking object
- `void lspg_lock_diffractionmeter_cb (lspg_query_queue_t *qqp, PGresult *pgr)`
Callback routine for a lock diffractionmeter query.
- `void lspg_lock_diffractionmeter_call ()`
Request that the database grab the diffractionmeter lock.
- `void lspg_lock_diffractionmeter_wait ()`
Wait for the diffractionmeter lock.

- void [lspg_lock_diffractionmeter_done](#) ()
Finish up the lock diffractionmeter call.
- void [lspg_lock_diffractionmeter_all](#) ()
Convenience function that combines lock diffractionmeter calls.
- void [lspg_lock_detector_init](#) ()
Initialize detector lock object.
- void [lspg_lock_detector_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
Callback for when the detector lock has been grabbed.
- void [lspg_lock_detector_call](#) ()
Request (demand) a detector lock.
- void [lspg_lock_detector_wait](#) ()
Wait for the detector lock.
- void [lspg_lock_detector_done](#) ()
Finish waiting.
- void [lspg_lock_detector_all](#) ()
Detector lock convenience function.
- void [lspg_seq_run_prep_init](#) ()
Initialize the data collection object.
- void [lspg_seq_run_prep_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
Callback for the seq_run_prep query.
- void [lspg_seq_run_prep_call](#) (long long skey, double [kappa](#), double [phi](#), double cx, double cy, double ax, double ay, double az)
queue up the seq_run_prep query
- void [lspg_seq_run_prep_wait](#) ()
Wait for seq run prep query to return.
- void [lspg_seq_run_prep_done](#) ()
Indicate we are done waiting.
- void [lspg_seq_run_prep_all](#) (long long skey, double [kappa](#), double [phi](#), double cx, double cy, double ax, double ay, double az)
Convenience function to call seq run prep.
- void [lspg_getcenter_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
Retrieve the data to center the crystal.
- void [lspg_getcenter_init](#) ()
Initialize getcenter object.
- void [lspg_getcenter_call](#) ()
Request a getcenter query.
- void [lspg_getcenter_wait](#) ()
Wait for a getcenter query to return.
- void [lspg_getcenter_done](#) ()
Done with getcenter query.
- void [lspg_getcenter_all](#) ()
Convenience function to complete synchronous getcenter query.
- void [lspg_nextaction_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
Queue the next MD2 instruction.
- void [lspg_cmd_cb](#) (lspg_query_queue_t *qqp, PGresult *pgr)
Send strings directly to PMAC queue.
- void [lspg_flush](#) ()
Flush psql output buffer (ie, send the query)
- void [lspg_send_next_query](#) ()
send the next queued query to the DB server
- void [lspg_receive](#) ()

- *Receive a result of a query.*
- void `lspg_sig_service` (struct pollfd *evt)
 - *Service a signal Signals here are treated as file descriptors and fits into our poll scheme.*
- void `lspg_pg_service` (struct pollfd *evt)
 - *I/O control to/from the postgresql server.*
- PQnoticeProcessor `lspg_notice_processor` (void *arg, const char *msg)
- void `lspg_pg_connect` ()
 - *Connect to the pg server.*
- void `lspg_next_state` ()
 - *Implements our state machine Does not strictly only set the next state as it also calls some functions that, perhaps, alters the state mid-function.*
- void * `lspg_worker` (void *dummy)
 - *The main loop for the lspg thread.*
- void `lspg_init` ()
 - *Initialize the lspg module.*
- void `lspg_run` ()
 - *Start 'er runnin'.*

Variables

- static int `ls_pg_state` = `LS_PG_STATE_INIT`
 - *State of the lspg state machine.*
- static struct timeval `lspg_time_sent` `now`
 - *used to ensure we do not inundate the db server with connection requests*
- static pthread_t `lspg_thread`
 - *our worker thread*
- static pthread_mutex_t `lspg_queue_mutex`
 - *keep the queue from getting tangled*
- static pthread_cond_t `lspg_queue_cond`
 - *keeps the queue from overflowing*
- static struct pollfd `lspgfd`
 - *our poll info*
- static `lspg_query_queue_t` `lspg_query_queue` [`LS_PG_QUERY_QUEUE_LENGTH`]
 - *Our query queue.*
- static unsigned int `lspg_query_queue_on` = 0
 - *Next position to add something to the queue.*
- static unsigned int `lspg_query_queue_off` = 0
 - *The last item still being used (on == off means nothing in queue)*
- static unsigned int `lspg_query_queue_reply` = 0
 - *The current item being digested.*
- static PGconn * `q` = NULL
 - *Database connector.*
- static PostgresPollingStatusType `lspg_connectPoll_response`
 - *Used to determine state while connecting.*
- static PostgresPollingStatusType `lspg_resetPoll_response`
 - *Used to determine state while reconnecting.*
- `lspg_nextshot_t` `lspg_nextshot`
 - *the nextshot object*
- `lspg_getcenter_t` `lspg_getcenter`
 - *the getcenter object*

- static [lspg_wait_for_detector_t lspg_wait_for_detector](#)
Instance of the detector timing object.
- static [lspg_lock_diffractionmeter_t lspg_lock_diffractionmeter](#)
- static [lspg_lock_detector_t lspg_lock_detector](#)
- static [lspg_seq_run_prep_t lspg_seq_run_prep](#)

5.4.1 Detailed Description

Postgresql support for the LS-CAT pgpmac project.

```
\date 2012
\author Keith Brister
\copyright All Rights Reserved
```

Database state machine

State	Description
-4	Initiate connection
-3	Poll until connection initialization is complete
-2	Initiate reset
-1	Poll until connection reset is complete
1	Idle (wait for a notify from the server)
2	Send a query to the server
3	Continue flushing a command to the server
4	Waiting for a reply

Definition in file [lspg.c](#).

5.4.2 Macro Definition Documentation

5.4.2.1 #define LS_PG_QUERY_QUEUE_LENGTH 16384

Queue length should be long enough that we do not ordinarily bump into the end We should be safe as long as the thread the adds stuff to the queue is not the one that removes it.

(And we can tolerate the adding thread being paused.)

Definition at line 60 of file [lspg.c](#).

5.4.2.2 #define LS_PG_STATE_IDLE 1

Definition at line 34 of file [lspg.c](#).

5.4.2.3 #define LS_PG_STATE_INIT -4

Definition at line 30 of file [lspg.c](#).

5.4.2.4 #define LS_PG_STATE_INIT_POLL -3

Definition at line 31 of file [lspg.c](#).

5.4.2.5 #define LS_PG_STATE_RECV 4

Definition at line 37 of file [lspg.c](#).

5.4.2.6 #define LS_PG_STATE_RESET -2

Definition at line 32 of file lspg.c.

5.4.2.7 #define LS_PG_STATE_RESET_POLL -1

Definition at line 33 of file lspg.c.

5.4.2.8 #define LS_PG_STATE_SEND 2

Definition at line 35 of file lspg.c.

5.4.2.9 #define LS_PG_STATE_SEND_FLUSH 3

Definition at line 36 of file lspg.c.

5.4.3 Typedef Documentation**5.4.3.1 typedef struct lspg_lock_detector_struct lspg_lock_detector_t**

lock detector object Implements detector lock for exposure control

5.4.3.2 typedef struct lspg_lock_diffractionmeter_struct lspg_lock_diffractionmeter_t

Object used to impliment locking the diffractometer Critical to exposure timing.

5.4.3.3 typedef struct lspgQueryQueueStruct lspg_query_queue_t

Store each query along with it's callback function.

All calls are asynchronous

5.4.3.4 typedef struct lspg_seq_run_prep_struct lspg_seq_run_prep_t

Data collection running object.

5.4.3.5 typedef struct lspg_wait_for_detector_struct lspg_wait_for_detector_t

Object that implements detector / spindle timing We use database locks for exposure control and this implements the md2 portion of this handshake.

5.4.4 Function Documentation**5.4.4.1 char** lspg_array2ptrs (char * a)**

returns a null terminated list of strings parsed from postgresql array

Definition at line 165 of file lspg.c.

```

    {
        char **rtn, *sp, *acums;
        int i, n, inquote, havebackslash, rtni;;
        int mxsz;

```

```

inquote      = 0;
havebackslash = 0;

// Despense with the null input condition before we complicate the code below
if( a == NULL || a[0] == 0)
    return NULL;

// Count the maximum number of strings
// Actual number will be less if there are quoted commas
//
n = 1;
for( i=0; a[i]; i++) {
    if( a[i] == ',' )
        n++;
}
//
// The maximum size of any string is the length of a (+1)
//
mxsz = strlen(a) + 1;

// This is the accumulation string to make up the array elements
acums = (char *)calloc( mxsz, sizeof( char));
if( acums == NULL) {
    // TODO: print or otherwise log this condition
    // out of memory
    exit( 1);
}

//
// allocate storage for the pointer array and the null terminator
//
rtn = (char **)calloc( n+1, sizeof( char *));
if( rtn == NULL) {
    // TODO: print or otherwise log this condition
    // out of memory
    exit( 1);
}
rtni = 0;

// Go through and create the individual strings
sp = acums;
*sp = 0;
if( a[0] != '{') {
    // oh no! This isn't an array after all!
    // Zounds!
    return NULL;
}
inquote = 0;
havebackslash = 0;
for( i=1; a[i] != 0; i++) {
    switch( a[i]) {
        case '"':
            if( havebackslash) {
                // a quoted quote. Cool
                //
                *(sp++) = a[i];
                *sp = 0;
                havebackslash = 0;
            } else {
                // Toggle the flag
                inquote = 1 - inquote;
            }
            break;

        case '\\':
            if( havebackslash) {
                *(sp++) = a[i];
                *sp = 0;
                havebackslash = 0;
            } else {
                havebackslash = 1;
            }
            break;

        case ',':
            if( inquote || havebackslash) {
                *(sp++) = a[i];
                *sp = 0;
                havebackslash = 0;
            } else {
                rtn[rtni++] = strdup( acums);
                sp = acums;
            }
            break;

        case '}':
    
```

```

    if( inquote || havebackslash) {
        *(sp++) = a[i];
        *sp = 0;
        havebackslash = 0;
    } else {
        rtn[rtni++] = strdup( acums);
        rtn[rtni] = NULL;
        return( rtn);
    }
    break;

default:
    *(sp++) = a[i];
    *sp = 0;
    havebackslash = 0;
}
//
// Getting here means the final '}' was missing
// Probably we should throw an error or log it or something.
//
rtn[rtni++] = strdup( acums);
rtn[rtni] = NULL;
return( rtn);
}

```

5.4.4.2 void lspg_blight_lut_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Back Light Lookup Table Callback Install the lookup table for the Back Light.

Parameters

in	<i>qqp</i>	Our query
in	<i>pgr</i>	The query's result

Definition at line 394 of file lspg.c.

```

{
    int i;

    pthread_mutex_lock( &(blight->mutex));

    blight->nlut = PQntuples( pgr)/2;
    blight->lut = calloc( 2*blight->nlut, sizeof(double));
    if( blight->lut == NULL) {
        lslogging_log_message( "Out of memory
        (lspg_blight_lut_cb)");
        pthread_mutex_unlock( &(blight->mutex));
        return;
    }

    for( i=0; i<PQntuples( pgr); i++) {
        blight->lut[i] = strtod( PQgetvalue( pgr, i, 0), NULL);
    }

    pthread_mutex_unlock( &(blight->mutex));
}

```

5.4.4.3 void lspg_cmd_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Send strings directly to PMAC queue.

Parameters

in	<i>qqp</i>	Our query
in	<i>pgr</i>	Our result

Definition at line 1095 of file lspg.c.

```

{

```

```

//
// Call back function assumes query results in zero or more commands to send
// to the PMAC
//
int i;
char *sp;

for( i=0; i<PQntuples( pgr); i++) {
    sp = PQgetvalue( pgr, i, 0);
    if( sp != NULL && *sp != 0) {
        lspmac_SockSendline( sp);
        //
        // Keep asking for more until
        // there are no commands left
        //
        // This should solve a potential problem where
        // more than one command is put on the queue for a given notify.
        //
        lspg_query_push( lspg_cmd_cb, "select
            pmac.md2_queue_next()");
    }
}
}

```

5.4.4.4 void lspg_flight_lut_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Front Light Lookup table query callback Install the lookup table for the Front Light.

Parameters

in	<i>qqp</i>	Our query
in	<i>pgr</i>	Our result object

Definition at line 366 of file lspg.c.

```

{
    int i;

    pthread_mutex_lock( &(flight->mutex));

    flight->nlut = PQntuples( pgr)/2;
    flight->lut = calloc( 2*flight->nlut, sizeof(double));
    if( flight->lut == NULL) {
        lslogging_log_message( "Out of memory
            (lspg_flight_lut_cb)");
        pthread_mutex_unlock( &(flight->mutex));
        return;
    }

    for( i=0; i<PQntuples( pgr); i++) {
        flight->lut[i] = strtod( PQgetvalue( pgr, i, 0), NULL);
    }

    pthread_mutex_unlock( &(flight->mutex));
}

```

5.4.4.5 void lspg_flush ()

Flush psql output buffer (ie, send the query)

Definition at line 1124 of file lspg.c.

```

{
    int err;

    err = PQflush( q);
    switch( err) {
        case -1:
            // an error occurred

            lslogging_log_message( "flush failed: %s",
                PQerrorMessage( q));
    }
}

```

```

    ls_pg_state = LS_PG_STATE_IDLE;
    //
    // We should probably reset the connection and start from scratch.
    // Probably the connection died.
    //
    break;

case 0:
    // goodness and joy.
    ls_pg_state = LS_PG_STATE_RECV;
    break;

case 1:
    // more sending to do
    ls_pg_state = LS_PG_STATE_SEND_FLUSH;
    break;
}
}

```

5.4.4.6 void lspg_getcenter_all ()

Convenience function to complete synchronous getcenter query.

Definition at line 1058 of file lspg.c.

```

{
    lspg_getcenter_call();
    lspg_getcenter_wait();
    lspg_getcenter_done();
}

```

5.4.4.7 void lspg_getcenter_call ()

Request a getcenter query.

Definition at line 1034 of file lspg.c.

```

{
    pthread_mutex_lock( &lspg_getcenter.mutex);
    lspg_getcenter.new_value_ready = 0;
    pthread_mutex_unlock( &lspg_getcenter.mutex);

    lspg_query_push( lspg_getcenter_cb, "SELECT *
        FROM px.getcenter2() ");
}

```

5.4.4.8 void lspg_getcenter_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Retrieve the data to center the crystal.

Definition at line 969 of file lspg.c.

```

{
    static int
        zoom_c, dcx_c, dcx_c, dax_c, day_c, daz_c;

    pthread_mutex_lock( &(lspg_getcenter.mutex));

    lspg_getcenter.no_rows_returned = PQntuples(
        pgr) <= 0;
    if( lspg_getcenter.no_rows_returned) {
        //
        // No particular reason this path should ever be taken
        // but if we don't get rows then we had better not move anything.
        //
        lspg_getcenter.new_value_ready = 1;
        pthread_cond_signal( &(lspg_getcenter.cond));
        pthread_mutex_unlock( &(lspg_getcenter.mutex));
        return;
    }
}

```



```

zoom_c = PQfnumber( pgr, "zoom");
dcx_c = PQfnumber( pgr, "dcx");
dcy_c = PQfnumber( pgr, "dcy");
dax_c = PQfnumber( pgr, "dax");
day_c = PQfnumber( pgr, "day");
daz_c = PQfnumber( pgr, "daz");

lspg_getcenter.zoom_isnull = PQgetisnull( pgr, 0,
    zoom_c);
if( lspg_getcenter.zoom_isnull == 0)
    lspg_getcenter.zoom = atoi( PQgetvalue( pgr, 0, zoom_c));

lspg_getcenter.dcx_isnull = PQgetisnull( pgr, 0,
    dcx_c);
if( lspg_getcenter.dcx_isnull == 0)
    lspg_getcenter.dcx = atof( PQgetvalue( pgr, 0, dcx_c));

lspg_getcenter.dcy_isnull = PQgetisnull( pgr, 0,
    dcy_c);
if( lspg_getcenter.dcy_isnull == 0)
    lspg_getcenter.dcy = atof( PQgetvalue( pgr, 0, dcy_c));

lspg_getcenter.dax_isnull = PQgetisnull( pgr, 0,
    dax_c);
if( lspg_getcenter.dax_isnull == 0)
    lspg_getcenter.dax = atof( PQgetvalue( pgr, 0, dax_c));

lspg_getcenter.day_isnull = PQgetisnull( pgr, 0,
    day_c);
if( lspg_getcenter.day_isnull == 0)
    lspg_getcenter.day = atof( PQgetvalue( pgr, 0, day_c));

lspg_getcenter.daz_isnull = PQgetisnull( pgr, 0,
    daz_c);
if( lspg_getcenter.daz_isnull == 0)
    lspg_getcenter.daz = atof( PQgetvalue( pgr, 0, daz_c));

lspg_getcenter.new_value_ready = 1;

pthread_cond_signal( &(lspg_getcenter.cond));
pthread_mutex_unlock( &(lspg_getcenter.mutex));
}

```

5.4.4.9 void lspg_getcenter_done ()

Done with getcenter query.

Definition at line 1052 of file lspg.c.

```

{
    pthread_mutex_unlock( &(lspg_getcenter.mutex));
}

```

5.4.4.10 void lspg_getcenter_init ()

Initialize getcenter object.

Definition at line 1026 of file lspg.c.

```

{
    memset( &lspg_getcenter, 0, sizeof( lspg_getcenter
    ));
    pthread_mutex_init( &(lspg_getcenter.mutex), NULL);
    pthread_cond_init( &(lspg_getcenter.cond), NULL);
}

```

5.4.4.11 void lspg_getcenter_wait ()

Wait for a getcenter query to return.

Definition at line 1044 of file lspg.c.

```

    {
pthread_mutex_lock( &(lspg_getcenter.mutex));
while( lspg_getcenter.new_value_ready == 0)
    pthread_cond_wait( &(lspg_getcenter.cond), &(
        lspg_getcenter.mutex));
}

```

5.4.4.12 void lspg_init ()

Initiallize the lspg module.

Definition at line 1615 of file lspg.c.

```

    {
pthread_mutex_init( &lspg_queue_mutex, NULL);
pthread_cond_init( &lspg_queue_cond, NULL);
lspg_nextshot_init();
lspg_getcenter_init();
lspg_wait_for_detector_init();
lspg_lock_diffractionmeter_init();
lspg_lock_detector_init();
}

```

5.4.4.13 void lspg_init_motors_cb (lspg_query_queue_t * qq, PGresult * pgr)

Motor initialization callback.

Parameters

in	<i>qq</i>	The query queue item used to call us
in	<i>pgr</i>	The postgresql result object

Definition at line 284 of file lspg.c.

```

    {
int i, j;
// uint32_t home_column;
uint32_t name_column;
char *sp;
lspmac_motor_t *lsdp;

name_column = PQfnumber( pgr, "mm_name");
if( name_column == -1)
    return;

// home_column = PQfnumber( pgr, "mm_home");

for( i=0; i<PQntuples( pgr); i++) {

    lsdp = NULL;
    for( j=0; j<lspmac_nmotors; j++) {
        if( strcmp(lspmac_motors[j].name, PQgetvalue( pgr, i,
            name_column)) == 0) {
            lsdp = &(lspmac_motors[j]);

            // lsdp->home = lspg_array2ptrs( PQgetvalue( pgr, i,
            home_column));
            // lsdp->lspg_initialized = 1;
            break;
        }
    }
    if( lsdp == NULL)
        continue;
}
}

```

5.4.4.14 void lspg_lock_detector_all ()

Detector lock convinence function.

Definition at line 881 of file lspg.c.

```

    {
        lspg_lock_detector_call();
        lspg_lock_detector_wait();
        lspg_lock_detector_done();
    }

```

5.4.4.15 void lspg_lock_detector_call ()

Request (demand) a detector lock.

Definition at line 857 of file lspg.c.

```

    {
        pthread_mutex_lock( &(lspg_lock_detector.mutex));
        lspg_lock_detector.new_value_ready = 0;
        pthread_mutex_unlock( &(lspg_lock_detector.mutex));

        lspg_query_push( lspg_lock_detector.cb, "
            SELECT px.lock_detector() ");
    }

```

5.4.4.16 void lspg_lock_detector.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Callback for when the detector lock has be grabbed.

Definition at line 848 of file lspg.c.

```

    {
        pthread_mutex_lock( &(lspg_lock_detector.mutex));
        lspg_lock_detector.new_value_ready = 1;
        pthread_cond_signal( &(lspg_lock_detector.cond));
        pthread_mutex_unlock( &(lspg_lock_detector.mutex));
    }

```

5.4.4.17 void lspg_lock_detector_done ()

Finish waiting.

Definition at line 875 of file lspg.c.

```

    {
        pthread_mutex_unlock( &(lspg_lock_detector.mutex));
    }

```

5.4.4.18 void lspg_lock_detector_init ()

Initialize detector lock object.

Definition at line 840 of file lspg.c.

```

    {
        lspg_lock_detector.new_value_ready = 0;
        pthread_mutex_init( &(lspg_lock_detector.mutex), NULL);
        pthread_cond_init( &(lspg_lock_detector.cond), NULL);
    }

```

5.4.4.19 void lspg_lock_detector_wait ()

Wait for the detector lock.

Definition at line 867 of file lspg.c.

```

{
pthread_mutex_lock( &(lspg_lock_detector.mutex));
while( lspg_lock_detector.new_value_ready ==
0)
pthread_cond_wait( &(lspg_lock_detector.cond), &(
lspg_lock_detector.mutex));
}

```

5.4.4.20 void lspg_lock_diffractionmeter_all ()

Convenience function that combines lock diffractionmeter calls.

Definition at line 822 of file lspg.c.

```

{
lspg_lock_diffractionmeter_call();
lspg_lock_diffractionmeter_wait();
lspg_lock_diffractionmeter_all();
}

```

5.4.4.21 void lspg_lock_diffractionmeter_call ()

Request that the database grab the diffractionmeter lock.

Definition at line 798 of file lspg.c.

```

{
pthread_mutex_lock( &(lspg_lock_diffractionmeter.mutex
));
lspg_lock_diffractionmeter.new_value_ready
= 0;
pthread_mutex_unlock( &(lspg_lock_diffractionmeter.
mutex));

lspg_query_push( lspg_lock_diffractionmeter_cb
, "SELECT px.lock_diffractionmeter()");
}

```

5.4.4.22 void lspg_lock_diffractionmeter_cb (lspg_query_queue_t * qq, PGresult * pgr)

Callback routine for a lock diffractionmeter query.

Definition at line 789 of file lspg.c.

```

{
pthread_mutex_lock( &(lspg_lock_diffractionmeter.mutex
));
lspg_lock_diffractionmeter.new_value_ready
= 1;
pthread_cond_signal( &(lspg_lock_diffractionmeter.cond
));
pthread_mutex_unlock( &(lspg_lock_diffractionmeter.
mutex));
}

```

5.4.4.23 void lspg_lock_diffractionmeter_done ()

Finish up the lock diffractionmeter call.

Definition at line 816 of file lspg.c.

```

    {
pthread_mutex_unlock( &(lspg_lock_diffractionmeter.
    mutex));
}

```

5.4.4.24 void lspg_lock_diffractionmeter_init ()

initialize the diffractionmeter locking object

Definition at line 781 of file lspg.c.

```

    {
lspg_lock_diffractionmeter.new_value_ready
    = 0;
pthread_mutex_init( &(lspg_lock_diffractionmeter.mutex
    ), NULL);
pthread_cond_init( &(lspg_lock_diffractionmeter.cond
    ), NULL);
}

```

5.4.4.25 void lspg_lock_diffractionmeter_wait ()

Wait for the diffractionmeter lock.

Definition at line 808 of file lspg.c.

```

    {
pthread_mutex_lock( &(lspg_lock_diffractionmeter.mutex
    ));
while( lspg_lock_diffractionmeter.new_value_ready
    == 0)
    pthread_cond_wait( &(lspg_lock_diffractionmeter.cond
    ), &(lspg_lock_diffractionmeter.mutex));
}

```

5.4.4.26 void lspg_next_state ()

Implements our state machine Does not strictly only set the next state as it also calls some functions that, perhaps, alters the state mid-function.

Definition at line 1484 of file lspg.c.

```

    {
//
// connect to the database
//
if( q == NULL ||
    lspg_state == LS_PG_STATE_INIT ||
    lspg_state == LS_PG_STATE_RESET ||
    lspg_state == LS_PG_STATE_INIT_POLL ||
    lspg_state == LS_PG_STATE_RESET_POLL)
    lspg_pg_connect( lspgfd);

if( lspg_state == LS_PG_STATE_IDLE &&
    lspg_query_queue_on != lspg_query_queue_off
    )
    lspg_state = LS_PG_STATE_SEND;

switch( lspg_state) {
case LS_PG_STATE_INIT_POLL:
    if( lspg_connectPoll_response ==

```

```

        PGRES_POLLING_WRITING)
        lspgfd.events = POLLOUT;
    else if( lspg_connectPoll_response ==
        PGRES_POLLING_READING)
        lspgfd.events = POLLIN;
    else
        lspgfd.events = 0;
    break;

case LS_PG_STATE_RESET_POLL:
    if( lspg_resetPoll_response == PGRES_POLLING_WRITING
        )
        lspgfd.events = POLLOUT;
    else if( lspg_resetPoll_response ==
        PGRES_POLLING_READING)
        lspgfd.events = POLLIN;
    else
        lspgfd.events = 0;
    break;

case LS_PG_STATE_IDLE:
case LS_PG_STATE_RECV:
    lspgfd.events = POLLIN;
    break;

case LS_PG_STATE_SEND:
case LS_PG_STATE_SEND_FLUSH:
    lspgfd.events = POLLOUT;
    break;

default:
    lspgfd.events = 0;
}
}

```

5.4.4.27 void lspg_nextaction.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Queue the next MD2 instruction.

Parameters

in	<i>qqp</i>	The query that generated this result
in	<i>pgr</i>	The result

Definition at line 1067 of file lspg.c.

```

{
    char *action;

    if( PQntuples( pgr) <= 0)
        return; // Note: nextaction should always return at least
                "noAction", so this branch should never be taken

    action = PQgetvalue( pgr, 0, 0); // next action only returns one row

    if( strcmp( action, "noAction") == 0)
        return;

    if( pthread_mutex_trylock( &md2cmds_mutex) == 0) {
        strncpy( md2cmds_cmd, action, MD2CMDS_CMD_LENGTH
            -1);
        md2cmds_cmd[MD2CMDS_CMD_LENGTH-1] = 0;
        pthread_cond_signal( &md2cmds_cond);
        pthread_mutex_unlock( &md2cmds_mutex);
    } else {
        lslogging_log_message( "MD2 command '%s' ignored.
            Already running '%s'", action, md2cmds_cmd);
    }
}
}

```

5.4.4.28 void lspg_nextshot.call ()

Queue up a nextshot query.

Definition at line 681 of file lspg.c.

```

    {
pthread_mutex_lock( &(lspg_nextshot.mutex));
lspg_nextshot.new_value_ready = 0;
pthread_mutex_unlock( &(lspg_nextshot.mutex));

lspg_query_push( lspg_nextshot_cb, "SELECT *
    FROM px.nextshot()");
}

```

5.4.4.29 void lspg_nextshot.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Next Shot Callback.

This is a long and tedious routine as there are a large number of variables returned. Suck it up. Return with the global variable lspg_nextshot set.

Parameters

in	<i>qqp</i>	Our nextshot query
in	<i>pgr</i>	result of the query

Definition at line 426 of file lspg.c.

```

    {
static int got_col_nums=0;
static int
    dsdir_c, dspid_c, dsowidth_c, dsoscaxis_c, dsexp_c, skey_c, sstart_c, sfn_c
    , dsphi_c,
    dsomega_c, dskappa_c, dsdist_c, dsnrng_c, dshpid_c, cx_c, cy_c, ax_c, ay_c,
    az_c,
    active_c, sindex_c, stype_c,
    dsowidth2_c, dsoscaxis2_c, dsexp2_c, sstart2_c, dsphi2_c, dsomega2_c,
    dskappa2_c, dsdist2_c, dsnrng2_c,
    cx2_c, cy2_c, ax2_c, ay2_c, az2_c, active2_c, sindex2_c, stype2_c;

pthread_mutex_lock( &(lspg_nextshot.mutex));

lspg_nextshot.no_rows_returned = PQntuples( pgr)
    <= 0;
if( lspg_nextshot.no_rows_returned) {
    lspg_nextshot.new_value_ready = 1;
    pthread_cond_signal( &(lspg_nextshot.cond));
    pthread_mutex_unlock( &(lspg_nextshot.mutex));
    return; // I guess there was no shot after all
}

if( got_col_nums == 0) {
    dsdir_c = PQfnumber( pgr, "dsdir");
    dspid_c = PQfnumber( pgr, "dspid");
    dsowidth_c = PQfnumber( pgr, "dsowidth");
    dsoscaxis_c = PQfnumber( pgr, "dsoscaxis");
    dsexp_c = PQfnumber( pgr, "dsexp");
    skey_c = PQfnumber( pgr, "skey");
    sstart_c = PQfnumber( pgr, "sstart");
    sfn_c = PQfnumber( pgr, "sfn");
    dsphi_c = PQfnumber( pgr, "dsphi");
    dsomega_c = PQfnumber( pgr, "dsomega");
    dskappa_c = PQfnumber( pgr, "dskappa");
    dsdist_c = PQfnumber( pgr, "dsdist");
    dsnrng_c = PQfnumber( pgr, "dsnrng");
    dshpid_c = PQfnumber( pgr, "dshpid");
    cx_c = PQfnumber( pgr, "cx");
    cy_c = PQfnumber( pgr, "cy");
    ax_c = PQfnumber( pgr, "ax");
    ay_c = PQfnumber( pgr, "ay");
    az_c = PQfnumber( pgr, "az");
    active_c = PQfnumber( pgr, "active");
    sindex_c = PQfnumber( pgr, "sindex");
    stype_c = PQfnumber( pgr, "stype");
    dsowidth2_c = PQfnumber( pgr, "dsowidth2");
    dsoscaxis2_c = PQfnumber( pgr, "dsoscaxis2");
    dsexp2_c = PQfnumber( pgr, "dsexp2");
    sstart2_c = PQfnumber( pgr, "sstart2");
    dsphi2_c = PQfnumber( pgr, "dsphi2");
    dsomega2_c = PQfnumber( pgr, "dsomega2");
    dskappa2_c = PQfnumber( pgr, "dskappa2");
    dsdist2_c = PQfnumber( pgr, "dsdist2");
    dsnrng2_c = PQfnumber( pgr, "dsnrng2");
}

```

```

    cx2_c      = PQfnumber( pgr, "cx2");
    cy2_c      = PQfnumber( pgr, "cy2");
    ax2_c      = PQfnumber( pgr, "ax2");
    ay2_c      = PQfnumber( pgr, "ay2");
    az2_c      = PQfnumber( pgr, "az2");
    active2_c   = PQfnumber( pgr, "active2");
    sindex2_c   = PQfnumber( pgr, "sindex2");
    stype2_c    = PQfnumber( pgr, "stype2");

    got_col_nums = 1;
}

//
// NULL string values come back as empty strings
// Mark the null flag but allocate the empty string anyway
//

lspg_nextshot.dmdir_isnull = PQgetisnull( pgr, 0,
    dmdir_c);
if( lspg_nextshot.dmdir != NULL)
    free( lspg_nextshot.dmdir);
lspg_nextshot.dmdir = strdup( PQgetvalue( pgr, 0, dmdir_c))
;

lspg_nextshot.dspid_isnull = PQgetisnull( pgr, 0,
    dspid_c);
if( lspg_nextshot.dspid != NULL)
    free( lspg_nextshot.dspid);
lspg_nextshot.dspid = strdup( PQgetvalue( pgr, 0, dspid_c))
;

lspg_nextshot.dsoscaxis_isnull = PQgetisnull(
    pgr, 0, dsoscaxis_c);
if( lspg_nextshot.dsoscaxis != NULL)
    free( lspg_nextshot.dsoscaxis);
lspg_nextshot.dsoscaxis = strdup( PQgetvalue( pgr, 0,
    dsoscaxis_c));

lspg_nextshot.dsoscaxis2_isnull = PQgetisnull(
    pgr, 0, dsoscaxis2_c);
if( lspg_nextshot.dsoscaxis2 != NULL)
    free( lspg_nextshot.dsoscaxis2);
lspg_nextshot.dsoscaxis2 = strdup( PQgetvalue( pgr, 0,
    dsoscaxis2_c));

lspg_nextshot.sfn_isnull = PQgetisnull(pgr, 0, sfn_c);
if( lspg_nextshot.sfn != NULL)
    free( lspg_nextshot.sfn);
lspg_nextshot.sfn = strdup( PQgetvalue( pgr, 0, sfn_c));

lspg_nextshot.stype_isnull = PQgetisnull( pgr, 0,
    stype_c);
if( lspg_nextshot.stype != NULL)
    free( lspg_nextshot.stype);
lspg_nextshot.stype = strdup( PQgetvalue( pgr, 0, stype_c))
;

lspg_nextshot.stype2_isnull = PQgetisnull( pgr, 0,
    stype2_c);
if( lspg_nextshot.stype2 != NULL)
    free( lspg_nextshot.stype2);
lspg_nextshot.stype2 = strdup( PQgetvalue( pgr, 0,
    stype2_c));

//
// Probably shouldn't try to convert null number values
//
lspg_nextshot.dsowidth_isnull = PQgetisnull( pgr,
    0, dsowidth_c);
if( lspg_nextshot.dsowidth_isnull == 0)
    lspg_nextshot.dsowidth = atof( PQgetvalue( pgr,0,
    dsowidth_c));

lspg_nextshot.dsexp_isnull = PQgetisnull( pgr, 0,
    dsexp_c);
if( lspg_nextshot.dsexp_isnull == 0)
    lspg_nextshot.dsexp = atof( PQgetvalue( pgr,0, dsexp_c
    ));

lspg_nextshot.sstart_isnull = PQgetisnull( pgr, 0,
    sstart_c);
if( lspg_nextshot.sstart_isnull == 0)
    lspg_nextshot.sstart = atof( PQgetvalue( pgr,0,
    sstart_c));

lspg_nextshot.dsphi_isnull = PQgetisnull( pgr, 0,

```



```

    dsphi_c);
if( lspg_nextshot.dsphi_isnull == 0)
    lspg_nextshot.dsphi = atof( PQgetvalue( pgr,0, dsphi_c
    ));

lspg_nextshot.dsomega_isnull = PQgetisnull( pgr, 0
    , dsoomega_c);
if( lspg_nextshot.dsomega_isnull == 0)
    lspg_nextshot.dsomega = atof( PQgetvalue( pgr,0,
    dsoomega_c));

lspg_nextshot.dskappa_isnull = PQgetisnull( pgr, 0
    , dskappa_c);
if( lspg_nextshot.dskappa_isnull == 0)
    lspg_nextshot.dskappa = atof( PQgetvalue( pgr,0,
    dskappa_c));

lspg_nextshot.dsdist_isnull = PQgetisnull( pgr, 0,
    dsdist_c);
if( lspg_nextshot.dsdist_isnull == 0)
    lspg_nextshot.dsdist = atof( PQgetvalue( pgr,0,
    dsdist_c));

lspg_nextshot.dsnrg_isnull = PQgetisnull( pgr, 0,
    dsnrg_c);
if( lspg_nextshot.dsnrg_isnull == 0)
    lspg_nextshot.dsnrg = atof( PQgetvalue( pgr,0, dsnrg_c
    ));

lspg_nextshot.cx_isnull = PQgetisnull( pgr, 0, cx_c);
if( lspg_nextshot.cx_isnull == 0)
    lspg_nextshot.cx = atof( PQgetvalue( pgr,0, cx_c));

lspg_nextshot.cy_isnull = PQgetisnull( pgr, 0, cy_c);
if( lspg_nextshot.cy_isnull == 0)
    lspg_nextshot.cy = atof( PQgetvalue( pgr,0, cy_c));

lspg_nextshot.ax_isnull = PQgetisnull( pgr, 0, ax_c);
if( lspg_nextshot.ax_isnull == 0)
    lspg_nextshot.ax = atof( PQgetvalue( pgr,0, ax_c));

lspg_nextshot.ay_isnull = PQgetisnull( pgr, 0, ay_c);
if( lspg_nextshot.ay_isnull == 0)
    lspg_nextshot.ay = atof( PQgetvalue( pgr,0, ay_c));

lspg_nextshot.az_isnull = PQgetisnull( pgr, 0, az_c);
if( lspg_nextshot.az_isnull == 0)
    lspg_nextshot.az = atof( PQgetvalue( pgr,0, az_c));

lspg_nextshot.active_isnull = PQgetisnull( pgr, 0,
    active_c);
if( lspg_nextshot.active_isnull == 0)
    lspg_nextshot.active = atoi( PQgetvalue( pgr, 0,
    active_c));

lspg_nextshot.sindex_isnull = PQgetisnull( pgr, 0,
    sindex_c);
if( lspg_nextshot.sindex_isnull == 0)
    lspg_nextshot.sindex = atoi( PQgetvalue( pgr, 0,
    sindex_c));

lspg_nextshot.dshpid_isnull = PQgetisnull( pgr, 0,
    dshpid_c);
if( lspg_nextshot.dshpid_isnull == 0)
    lspg_nextshot.dshpid = atoi( PQgetvalue( pgr, 0,
    dshpid_c));

lspg_nextshot.skey_isnull = PQgetisnull( pgr, 0,
    skey_c);
if( lspg_nextshot.skey_isnull == 0)
    lspg_nextshot.skey = atoll( PQgetvalue( pgr, 0, skey_c)
    );

lspg_nextshot.dsowidth2_isnull = PQgetisnull(
    pgr, 0, dsowidth2_c);
if( lspg_nextshot.dsowidth2_isnull == 0)
    lspg_nextshot.dsowidth2 = atof( PQgetvalue( pgr,0,
    dsowidth2_c));

lspg_nextshot.dsexp2_isnull = PQgetisnull( pgr, 0,
    dsexp2_c);
if( lspg_nextshot.dsexp2_isnull == 0)
    lspg_nextshot.dsexp2 = atof( PQgetvalue( pgr,0,
    dsexp2_c));

lspg_nextshot.sstart2_isnull = PQgetisnull( pgr, 0
    , sstart2_c);

```

```

if( lspg_nextshot.sstart2_isnull == 0)
    lspg_nextshot.sstart2 = atof( PQgetvalue( pgr,0,
        sstart2_c));

lspg_nextshot.dsphi2_isnull = PQgetisnull( pgr, 0,
    dsphi2_c);
if( lspg_nextshot.dsphi2_isnull == 0)
    lspg_nextshot.dsphi2 = atof( PQgetvalue( pgr,0,
        dsphi2_c));

lspg_nextshot.dsomega2_isnull = PQgetisnull( pgr,
    0, dsomega2_c);
if( lspg_nextshot.dsomega2_isnull == 0)
    lspg_nextshot.dsomega2 = atof( PQgetvalue( pgr,0,
        dsomega2_c));

lspg_nextshot.dskappa2_isnull = PQgetisnull( pgr,
    0, dskappa2_c);
if( lspg_nextshot.dskappa2_isnull == 0)
    lspg_nextshot.dskappa2 = atof( PQgetvalue( pgr,0,
        dskappa2_c));

lspg_nextshot.dsdist2_isnull = PQgetisnull( pgr, 0
    , dsdist2_c);
if( lspg_nextshot.dsdist2_isnull == 0)
    lspg_nextshot.dsdist2 = atof( PQgetvalue( pgr,0,
        dsdist2_c));

lspg_nextshot.dsnrg2_isnull = PQgetisnull( pgr, 0,
    dsnrg2_c);
if( lspg_nextshot.dsnrg2_isnull == 0)
    lspg_nextshot.dsnrg2 = atof( PQgetvalue( pgr,0,
        dsnrg2_c));

lspg_nextshot.cx2_isnull = PQgetisnull( pgr, 0, cx2_c)
;
if( lspg_nextshot.cx2_isnull == 0)
    lspg_nextshot.cx2 = atof( PQgetvalue( pgr,0, cx2_c));

lspg_nextshot.cy2_isnull = PQgetisnull( pgr, 0, cy2_c)
;
if( lspg_nextshot.cy2_isnull == 0)
    lspg_nextshot.cy2 = atof( PQgetvalue( pgr,0, cy2_c));

lspg_nextshot.ax2_isnull = PQgetisnull( pgr, 0, ax2_c)
;
if( lspg_nextshot.ax2_isnull == 0)
    lspg_nextshot.ax2 = atof( PQgetvalue( pgr,0, ax2_c));

lspg_nextshot.ay2_isnull = PQgetisnull( pgr, 0, ay2_c)
;
if( lspg_nextshot.ay2_isnull == 0)
    lspg_nextshot.ay2 = atof( PQgetvalue( pgr,0, ay2_c));

lspg_nextshot.az2_isnull = PQgetisnull( pgr, 0, az2_c)
;
if( lspg_nextshot.az2_isnull == 0)
    lspg_nextshot.az2 = atof( PQgetvalue( pgr,0, az2_c));

lspg_nextshot.active2_isnull = PQgetisnull( pgr, 0
    , active2_c);
if( lspg_nextshot.active2_isnull == 0)
    lspg_nextshot.active2 = atoi( PQgetvalue( pgr, 0,
        active2_c));

lspg_nextshot.sindex2_isnull = PQgetisnull( pgr, 0
    , sindex2_c);
if( lspg_nextshot.sindex2_isnull == 0)
    lspg_nextshot.sindex2 = atoi( PQgetvalue( pgr, 0,
        sindex2_c));

lspg_nextshot.new_value_ready = 1;

pthread_cond_signal( &(lspg_nextshot.cond));
pthread_mutex_unlock( &(lspg_nextshot.mutex));
}

```

5.4.4.30 void lspg_nextshot.done ()

Called when the next shot query has been processed.

Definition at line 699 of file lspg.c.

```

    {
        pthread_mutex_unlock( &(lspg_nextshot.mutex));
    }

```

5.4.4.31 void lspg_nextshot_init ()

Initialize the nextshot variable, mutex, and condition.

Definition at line 673 of file lspg.c.

```

    {
        memset( &lspg_nextshot, 0, sizeof( lspg_nextshot));
        pthread_mutex_init( &(lspg_nextshot.mutex), NULL);
        pthread_cond_init( &(lspg_nextshot.cond), NULL);
    }

```

5.4.4.32 void lspg_nextshot_wait ()

Wait for the next shot query to get processed.

Definition at line 691 of file lspg.c.

```

    {
        pthread_mutex_lock( &(lspg_nextshot.mutex));
        while( lspg_nextshot.new_value_ready == 0)
            pthread_cond_wait( &(lspg_nextshot.cond), &(lspg_nextshot
                .mutex));
    }

```

5.4.4.33 PQnoticeProcessor lspg_notice_processor (void * arg, const char * msg)

Definition at line 1379 of file lspg.c.

```

    {
        lslogging_log_message( "lspg: %s", msg);
    }

```

5.4.4.34 void lspg_pg_connect ()

Connect to the pg server.

Definition at line 1385 of file lspg.c.

```

    {
        PGresult *pgr;
        int wait_interval = 1;
        int connection_init = 0;
        int i, err;

        if( q == NULL)
            ls_pg_state = LS_PG_STATE_INIT;

        switch( ls_pg_state) {
        case LS_PG_STATE_INIT:

            if( lspg_time_sent.tv_sec != 0) {
                //
                // Reality check: if it's less the about 10 seconds since the last failed
                // attempt
                // the just chill.
                //
                gettimeofday( &now, NULL);
                if( now.tv_sec - lspg_time_sent.tv_sec < 10) {
                    return;
                }
            }
        }
    }

```

```

q = PQconnectStart( "dbname=ls user=lsuser hostaddr=10.1.0.3");
if( q == NULL) {
    lslogging_log_message( "Out of memory
        (lspg_pg_connect)");
    exit( -1);
}

err = PQstatus( q);
if( err == CONNECTION_BAD) {
    lslogging_log_message( "Trouble connecting to
        database");

    gettimeofday( &lspg_time_sent, NULL);
    return;
}
err = PQsetnonblocking( q, 1);
if( err != 0) {
    lslogging_log_message( "Odd, could not set database
        connection to nonblocking");
}

ls_pg_state = LS_PG_STATE_INIT_POLL;
lspg_connectPoll_response = PGRES_POLLING_WRITING;
//
// set up the connection for poll
//
lspgfd.fd = PQsocket( q);
break;

case LS_PG_STATE_INIT_POLL:
    if( lspg_connectPoll_response ==
        PGRES_POLLING_FAILED) {
        PQfinish( q);
        q = NULL;
        ls_pg_state = LS_PG_STATE_INIT;
    } else if( lspg_connectPoll_response ==
        PGRES_POLLING_OK) {
        PQsetNoticeProcessor( q, (PQnoticeProcessor)lspg_notice_processor
            , NULL);
        lspg_query_push( lspg_init_motors_cb, "
            select * from pmac.md2_getmotors()");
        lspg_query_push( NULL, "select pmac.md2_init()");
        lspg_query_push( lspg_zoom_lut_cb, "SELECT
            * FROM pmac.md2_zoom_lut()");
        lspg_query_push( lspg_flight_lut_cb, "
            SELECT * FROM pmac.md2_flight_lut()");
        lspg_query_push( lspg_blight_lut_cb, "
            SELECT * FROM pmac.md2_blight_lut()");
        lspg_query_push( lspg_scint_lut_cb, "
            SELECT * FROM pmac.md2_scint_lut()");

        ls_pg_state = LS_PG_STATE_IDLE;
    }
    break;

case LS_PG_STATE_RESET:
    err = PQresetStart( q);
    if( err == 0) {
        PQfinish( q);
        q = NULL;
        ls_pg_state = LS_PG_STATE_INIT;
    } else {
        ls_pg_state = LS_PG_STATE_RESET_POLL;
        lspg_resetPoll_response = PGRES_POLLING_WRITING;
    }
    break;

case LS_PG_STATE_RESET_POLL:
    if( lspg_resetPoll_response == PGRES_POLLING_FAILED)
    {
        PQfinish( q);
        q = NULL;
        ls_pg_state = LS_PG_STATE_INIT;
    } else if( lspg_resetPoll_response ==
        PGRES_POLLING_OK) {
        lspg_query_push( lspg_init_motors_cb, "
            select * from pmac.md2_getmotors()");
        lspg_query_push( NULL, "select pmac.md2_init()");
        ls_pg_state = LS_PG_STATE_IDLE;
    }
    break;
}
}

```

5.4.4.35 void lspg_pg_service (struct pollfd * evt)

I/O control to/from the postgresql server.

Parameters

in	evt	The pollfd object that we are responding to
----	-----	---

Definition at line 1284 of file lspg.c.

```

    {
//
// Currently just used to check for notifies
// Other socket communication is done synchronously
//

if( evt->revents & POLLIN) {
    int err;

    if( ls_pg_state == LS_PG_STATE_INIT_POLL) {
        lspg_connectPoll_response = PQconnectPoll( q);
        if( lspg_connectPoll_response ==
            PGRES_POLLING_FAILED) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

    if( ls_pg_state == LS_PG_STATE_RESET_POLL)
    {
        lspg_resetPoll_response = PQresetPoll( q);
        if( lspg_resetPoll_response ==
            PGRES_POLLING_FAILED) {
            ls_pg_state = LS_PG_STATE_RESET;
        }
        return;
    }

//
// if in IDLE or RECV we need to call consumeInput first
//
    if( ls_pg_state == LS_PG_STATE_IDLE) {
        err = PQconsumeInput( q);
        if( err != 1) {
            lslogging_log_message( "consume input failed: %s",
                PQerrorMessage( q));
            ls_pg_state == LS_PG_STATE_RESET;
            return;
        }
    }

    if( ls_pg_state == LS_PG_STATE_RECV) {
        lspg_receive();
    }

//
// Check for notifies regardless of our state
// Push as many requests as we have notifies.
//
    {
        PGnotify *pgn;

        while( 1) {
            pgn = PQnotifies( q);
            if( pgn == NULL)
                break;

            if( strstr( pgn->relname, "_pmac") != NULL) {
                lspg_query_push( lspg_cmd_cb, "SELECT
                pmac.md2_queue_next()");
            } else if (strstr( pgn->relname, "_diff") != NULL) {
                lspg_query_push( lspg_nextaction_cb,
                "SELECT action FROM px.nextaction()");
            }
            PQfreemem( pgn);
        }
    }

    if( evt->revents & POLLOUT) {

        if( ls_pg_state == LS_PG_STATE_INIT_POLL) {

```

```

    lspg_connectPoll_response = PQconnectPoll( q);
    if( lspg_connectPoll_response ==
    PGRES_POLLING_FAILED) {
        ls_pg_state = LS_PG_STATE_RESET;
    }
    return;
}

if( ls_pg_state == LS_PG_STATE_RESET_POLL)
{
    lspg_resetPoll_response = PQresetPoll( q);
    if( lspg_resetPoll_response ==
    PGRES_POLLING_FAILED) {
        ls_pg_state = LS_PG_STATE_RESET;
    }
    return;
}

if( ls_pg_state == LS_PG_STATE_SEND) {
    lspg_send_next_query();
}

if( ls_pg_state == LS_PG_STATE_SEND_FLUSH)
{
    lspg_flush();
}
}
}

```

5.4.4.36 lspg_query_queue_t* lspg_query_next()

Return the next item in the postgresql queue.

If there is an item left in the queue then it is returned. Otherwise, NULL is returned.

Definition at line 79 of file lspg.c.

```

{
    lspg_query_queue_t *rtn;

    pthread_mutex_lock( &lspg_queue_mutex);

    if( lspg_query_queue_off == lspg_query_queue_on
    )
        // Queue is empty
        rtn = NULL;
    else {
        rtn = &(lspg_query_queue[ (lspg_query_queue_off
        ++ ) % LS_PG_QUERY_QUEUE_LENGTH]);
        pthread_cond_signal( &lspg_queue_cond);
    }
    pthread_mutex_unlock( &lspg_queue_mutex);

    return rtn;
}

```

5.4.4.37 void lspg_query_push(void(*) (lspg_query_queue_t *, PGresult *) cb, char * fmt, ...)

Place a query on the queue.

Parameters

in	<i>cb</i>	Our callback function that deals with the response
in	<i>fmt</i>	Printf style function to generate the query

Definition at line 132 of file lspg.c.

```

{
    int idx;
    va_list arg_ptr;

    pthread_mutex_lock( &lspg_queue_mutex);

```

```

//
// Pause the thread while we service the queue
//
while( lspg_query_queue_on + 1 == lspg_query_queue_off
    ) {
    pthread_cond_wait( &lspg_queue_cond, &lspg_queue_mutex
    );
}

idx = lspg_query_queue_on % LS_PG_QUERY_QUEUE_LENGTH
    ;

va_start( arg_ptr, fmt);
vsnprintf( lspg_query_queue[idx].qs,
    LS_PG_QUERY_STRING_LENGTH-1, fmt, arg_ptr);
va_end( arg_ptr);

lspg_query_queue[idx].qs[LS_PG_QUERY_STRING_LENGTH
    - 1] = 0;
lspg_query_queue[idx].onResponse = cb;
lspg_query_queue_on++;

pthread_kill( lspg_thread, SIGUSR1);
pthread_mutex_unlock( &lspg_queue_mutex);
};

```

5.4.4.38 void lspg_query_reply_next ()

Remove the oldest item in the queue.

this is called only when there is nothing else to service the reply: this pop does not return anything. We use the ...reply_peek function to return the next item in the reply queue

Definition at line 103 of file lspg.c.

```

{

pthread_mutex_lock( &lspg_queue_mutex);

if( lspg_query_queue_reply != lspg_query_queue_on
    )
    lspg_query_queue_reply++;

pthread_mutex_unlock( &lspg_queue_mutex);
}

```

5.4.4.39 lspg_query_queue_t* lspg_query_reply_peek ()

Return the next item in the reply queue but don't pop it since we may need it more than once.

Call `lspg_query_reply_next()` when done.

Definition at line 116 of file lspg.c.

```

{

lspg_query_queue_t *rtn;

pthread_mutex_lock( &lspg_queue_mutex);

if( lspg_query_queue_reply == lspg_query_queue_on
    )
    rtn = NULL;
else
    rtn = &(lspg_query_queue[ (lspg_query_queue_reply
        ) % LS_PG_QUERY_QUEUE_LENGTH]);

pthread_mutex_unlock( &lspg_queue_mutex);
return rtn;
}

```

5.4.4.40 void lspg_receive ()

Receive a result of a query.

Definition at line 1201 of file lspg.c.

```

    {
        PGresult *pgr;
        lspg_query_queue_t *qqp;
        int err;

        err = PQconsumeInput( q );
        if( err != 1 ) {
            lslogging_log_message( "consume input failed: %s",
                PQerrorMessage( q ));
            ls_pg_state == LS_PG_STATE_RESET;
            return;
        }

        //
        // We must call PQgetResult until it returns NULL before sending the next
        // query
        // This implies that only one query can ever be active at a time and our
        // queue
        // management should be simple
        //
        // We should be in the LS_PG_STATE_RECV here
        //

        while( !PQisBusy( q ) ) {
            pgr = PQgetResult( q );
            if( pgr == NULL ) {
                lspg_query_reply_next();
                //
                // we are now done reading the response from the database
                //
                ls_pg_state = LS_PG_STATE_IDLE;
                break;
            } else {
                ExecStatusType es;

                qqp = lspg_query_reply_peek();
                es = PQresultStatus( pgr );

                if( es != PGRES_COMMAND_OK && es != PGRES_TUPLES_OK ) {
                    char *emess;
                    emess = PQresultErrorMessage( pgr );
                    if( emess != NULL && emess[0] != 0 ) {
                        lslogging_log_message( "Error from query '%s':\n
%s", qqp->qid, emess );
                    }
                } else {
                    //
                    // Deal with the response
                    //
                    // If the response is likely to take awhile we should probably
                    // add a new state and put something in the main loop to run the
                    // onResponse
                    // routine in the main loop. For now, though, we only expect very
                    // brief onResponse routines
                    //
                    if( qqp != NULL && qqp->onResponse != NULL )
                        qqp->onResponse( qqp, pgr );
                }
                PQclear( pgr );
            }
        }
    }
}

```

5.4.4.41 void lspg_run ()

Start 'er runnin'.

Definition at line 1627 of file lspg.c.

```

    {
        pthread_create( &lspg_thread, NULL, lspg_worker, NULL );
    }
}

```


5.4.4.42 void lspg_scint_lut.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Parameters

in	<i>qqp</i>	Our query
in	<i>pgr</i>	Our result object

Definition at line 342 of file lspg.c.

```

{
    int i;
    pthread_mutex_lock( &(fscint->mutex));

    fscint->nlut = PQntuples( pgr)/2;
    fscint->lut = calloc( 2*fscint->nlut, sizeof( double));
    if( fscint->lut == NULL) {
        lslogging_log_message( "lspg_scint_lut.cb: Out of
            memory");
        pthread_mutex_unlock( &(fscint->mutex));
    }

    for( i=0; i<PQntuples( pgr); i++) {
        fscint->lut[i] = strtod( PQgetvalue( pgr, i, 0), NULL);
    }

    pthread_mutex_unlock( &(fscint->mutex));
}

```

5.4.4.43 void lspg_send_next_query ()

send the next queued query to the DB server

Definition at line 1154 of file lspg.c.

```

{
    //
    // Normally we should be in the "send" state
    // but we can also send if we are servicing
    // a reply
    //
    lspg_query_queue_t *qqp;
    int err;

    qqp = lspg_query_next();
    if( qqp == NULL) {
        //
        // A send without a query? Should never happen.
        // But at least we shouldn't segfault if it does.
        //
        return;
    }

    if( qqp->qs[0] == 0) {
        //
        // Do we really have to check this case?
        // It would only come up if we stupidly pushed an empty query string
        // or ran off the end of the queue
        //
        lslogging_log_message( "Popped empty query string.
            Probably bad things are going on.");

        lspg_query_reply_next();
        ls_pg_state = LS_PG_STATE_IDLE;
    } else {
        err = PQsendQuery( q, qqp->qs);
        if( err == 0) {
            lslogging_log_message( "query failed: %s\n",
                PQerrorMessage( q));

            //
            // Don't wait for a reply, just reset the connection
            //
            lspg_query_reply_next();
            ls_pg_state == LS_PG_STATE_RESET;
        } else {
            ls_pg_state = LS_PG_STATE_SEND_FLUSH;
        }
    }
}

```

5.4.4.44 void `lspg_seq_run_prep_all` (long long *skey*, double *kappa*, double *phi*, double *cx*, double *cy*, double *ax*, double *ay*, double *az*)

Convenience function to call seq run prep.

Parameters

in	<i>skey</i>	px.shots key for this image
in	<i>kappa</i>	current kappa postion
in	<i>phi</i>	current phi postition
in	<i>cx</i>	current center table x
in	<i>cy</i>	current center table y
in	<i>ax</i>	current alignment table x
in	<i>ay</i>	current alignment table y
in	<i>az</i>	current alignment table z

Definition at line 952 of file `lspg.c`.

```

{
    lspg_seq_run_prep_call( skey, kappa, phi, cx,
        cy, ax, ay, az);
    lspg_seq_run_prep_wait();
    lspg_seq_run_prep_done();
}

```

5.4.4.45 void `lspg_seq_run_prep_call` (long long *skey*, double *kappa*, double *phi*, double *cx*, double *cy*, double *ax*, double *ay*, double *az*)

queue up the `seq_run_prep` query

Parameters

in	<i>skey</i>	px.shots key for this image
in	<i>kappa</i>	current kappa postion
in	<i>phi</i>	current phi postition
in	<i>cx</i>	current center table x
in	<i>cy</i>	current center table y
in	<i>ax</i>	current alignment table x
in	<i>ay</i>	current alignment table y
in	<i>az</i>	current alignment table z

Definition at line 918 of file `lspg.c`.

```

{
    pthread_mutex_lock( &(amp;lspg_seq_run_prep.mutex));
    lspg_seq_run_prep.new_value_ready = 0;
    pthread_mutex_unlock( &(amp;lspg_seq_run_prep.mutex));

    lspg_query_push( lspg_seq_run_prep_cb, "
        SELECT px.seq_run_prep( %lld, %.3f, %.3f, %.3f, %.3f, %.3f, %.3f, %.3f)",
        skey, kappa, phi, cx, cy, ax, ay, az);
}

```

5.4.4.46 void `lspg_seq_run_prep.cb` (`lspg_query_queue_t` * *qqp*, `PGresult` * *pgr*)

Callback for the `seq_run_prep` query.

Parameters

in	<i>qqp</i>	The query item that generated this callback
in	<i>pgr</i>	The result of the query

Definition at line 906 of file lspg.c.

```

    {
pthread_mutex_lock( &(lspg_seq_run_prep.mutex));
lspg_seq_run_prep.new_value_ready = 1;
pthread_cond_signal( &(lspg_seq_run_prep.cond));
pthread_mutex_unlock( &(lspg_seq_run_prep.mutex));
}

```

5.4.4.47 void lspg_seq_run_prep.done ()

Indicate we are done waiting.

Definition at line 946 of file lspg.c.

```

    {
pthread_mutex_unlock( &(lspg_seq_run_prep.mutex));
}

```

5.4.4.48 void lspg_seq_run_prep.init ()

Initialize the data collection object.

Definition at line 898 of file lspg.c.

```

    {
lspg_seq_run_prep.new_value_ready = 0;
pthread_mutex_init( &(lspg_seq_run_prep.mutex), NULL);
pthread_cond_init( &(lspg_seq_run_prep.cond), NULL);
}

```

5.4.4.49 void lspg_seq_run_prep.wait ()

Wait for seq run prep query to return.

Definition at line 938 of file lspg.c.

```

    {
pthread_mutex_lock( &(lspg_seq_run_prep.mutex));
while( lspg_seq_run_prep.new_value_ready == 0
    )
    pthread_cond_wait( &(lspg_seq_run_prep.cond), &(
        lspg_seq_run_prep.mutex));
}

```

5.4.4.50 void lspg_sig_service (struct pollfd * evt)

Service a signal Signals here are treated as file descriptors and fits into our poll scheme.

Parameters

in	evt	The pollfd object that triggered this call
----	-----	--

Definition at line 1262 of file lspg.c.

```

    {
struct signalfd_siginfo fdsi;

//
// Really, we don't care about the signal,
// it's just used to drop out of the poll
// function when there is something for us

```

```

// to do that didn't involve something coming
// from our postgresql server.
//
// This is accomplished by the query_push function
// to notify us that a new query is ready.
//

read( evt->fd, &fdsi, sizeof( struct signalfd_siginfo));
}

```

5.4.4.51 void lspg_wait_for_detector.all ()

Combined call to wait for the detector.

Definition at line 762 of file lspg.c.

```

{
    lspg_wait_for_detector_call();
    lspg_wait_for_detector_wait();
    lspg_wait_for_detector_done();
}

```

5.4.4.52 void lspg_wait_for_detector.call ()

initiate the wait for detector query

Definition at line 736 of file lspg.c.

```

{
    pthread_mutex_lock( &(lspg_wait_for_detector.mutex
    ));
    lspg_wait_for_detector.new_value_ready =
        0;
    pthread_mutex_unlock( &(lspg_wait_for_detector.mutex
    ));

    lspg_query_push( lspg_wait_for_detector.cb
        , "SELECT px.lock_detector_test_block()");
}

```

5.4.4.53 void lspg_wait_for_detector.cb (lspg_query_queue_t * qqp, PGresult * pgr)

Callback for the wait for detector query.

Definition at line 727 of file lspg.c.

```

{
    pthread_mutex_lock( &(lspg_wait_for_detector.mutex
    ));
    lspg_wait_for_detector.new_value_ready =
        1;
    pthread_cond_signal( &(lspg_wait_for_detector.cond
    ));
    pthread_mutex_unlock( &(lspg_wait_for_detector.mutex
    ));
}

```

5.4.4.54 void lspg_wait_for_detector.done ()

Done waiting for the detector.

Definition at line 755 of file lspg.c.

```

{
    pthread_mutex_unlock( &(lspg_wait_for_detector.mutex
    ));
}

```

5.4.4.55 void lspg_wait_for_detector_init ()

initialize the detector timing object

Definition at line 719 of file lspg.c.

```

    {
        lspg_wait_for_detector.new_value_ready =
            0;
        pthread_mutex_init( &(lspg_wait_for_detector.mutex
            ), NULL);
        pthread_cond_init( &(lspg_wait_for_detector.cond),
            NULL);
    }

```

5.4.4.56 void lspg_wait_for_detector_wait ()

Pause the calling thread until the detector is ready Called by the MD2 thread.

Definition at line 747 of file lspg.c.

```

    {
        pthread_mutex_lock( &(lspg_wait_for_detector.mutex
            ));
        while( lspg_wait_for_detector.new_value_ready
            == 0)
            pthread_cond_wait( &(lspg_wait_for_detector.cond)
                , &(lspg_wait_for_detector.mutex));
    }

```

5.4.4.57 void* lspg_worker (void * dummy)

The main loop for the lspg thread.

Parameters

in	<i>dummy</i>	Required by pthreads but unused
----	--------------	---------------------------------

Definition at line 1535 of file lspg.c.

```

    {
        static struct pollfd fda[2]; // 0=signal handler, 1=pg socket
        static int nfda = 0;
        static sigset_t our_sigset;
        int sigfd;

        sigemptyset( &our_sigset);
        sigaddset( &our_sigset, SIGUSR1);

        //
        // block ordinary signal mechanism
        //
        sigprocmask(SIG_BLOCK, &our_sigset, NULL);

        fda[0].fd = signalfd( -1, &our_sigset, SFD_NONBLOCK);
        if( fda[0].fd == -1) {
            char *es;

            es = strerror( errno);
            lslogging_log_message( "Signalfd trouble: %s", es);
        }
        fda[0].events = POLLIN;

        //
        // make sure file descriptor is not legal until it's been connected
        //
        lspgfd.fd = -1;

        while( 1) {

```

```

    int pollrtn;
    int poll_timeout_ms;

    lspg_next_state();

    if( lspgfd.fd == -1) {
        //
        // Here a connection to the database is not established.
        // Periodically try again. Should possibly arrange to reconnect
        // to signalfd but that's unlikely to be necessary.
        //
        nfda = 1;
        poll_timeout_ms = 10000;
        fda[1].revents = 0;
    } else {
        //
        // Arrange to peacefully do nothing until either the pg server sends us
        // something
        // or someone pushes something onto our queue
        //
        nfda = 2;
        fda[1].fd      = lspgfd.fd;
        fda[1].events  = lspgfd.events;
        fda[1].revents = 0;
        poll_timeout_ms = -1;
    }

    pollrtn = poll( fda, nfda, poll_timeout_ms);

    if( pollrtn && fda[0].revents) {
        lspg_sig_service( &(fda[0]));
        pollrtn--;
    }
    if( pollrtn && fda[1].revents) {
        lspg_pg_service( &(fda[1]));
        pollrtn--;
    }
}
}

```

5.4.4.58 void lspg_zoom_lut_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Zoom motor look up table callback.

Parameters

in	<i>qqp</i>	the queue item responsible for calling us
in	<i>pgr</i>	The Postgresql result object

Definition at line 319 of file lspg.c.

```

{
    int i;

    pthread_mutex_lock( &(zoom->mutex));

    zoom->nlut = PQntuples( pgr)/2;
    zoom->lut = calloc( 2+zoom->nlut, sizeof(double));
    if( zoom->lut == NULL) {
        lslogging_log_message( "Out of memory
        (lspg_zoom_lut_cb)");
        pthread_mutex_unlock( &(zoom->mutex));
        return;
    }

    for( i=0; i<PQntuples( pgr); i++) {
        zoom->lut[i] = strtod( PQgetvalue( pgr, i, 0), NULL);
    }

    pthread_mutex_unlock( &(zoom->mutex));
}

```

5.4.5 Variable Documentation

5.4.5.1 `int ls_pg_state = LS_PG_STATE_INIT` `[static]`

State of the lspg state machine.

Definition at line 39 of file lspg.c.

5.4.5.2 `PostgresPollingStatusType lspg_connectPoll_response` `[static]`

Used to determine state while connecting.

Definition at line 69 of file lspg.c.

5.4.5.3 `lspg_getcenter_t lspg_getcenter`

the getcenter object

Definition at line 73 of file lspg.c.

5.4.5.4 `lspg_lock_detector_t lspg_lock_detector` `[static]`

Definition at line 836 of file lspg.c.

5.4.5.5 `lspg_lock_diffractionmeter_t lspg_lock_diffractionmeter` `[static]`

Definition at line 777 of file lspg.c.

5.4.5.6 `lspg_nextshot_t lspg_nextshot`

the nextshot object

Definition at line 72 of file lspg.c.

5.4.5.7 `lspg_query_queue_t lspg_query_queue[LS_PG_QUERY_QUEUE_LENGTH]` `[static]`

Our query queue.

Definition at line 61 of file lspg.c.

5.4.5.8 `unsigned int lspg_query_queue_off = 0` `[static]`

The last item still being used (on == off means nothing in queue)

Definition at line 63 of file lspg.c.

5.4.5.9 `unsigned int lspg_query_queue_on = 0` `[static]`

Next position to add something to the queue.

Definition at line 62 of file lspg.c.

5.4.5.10 `unsigned int lspg_query_queue_reply = 0` `[static]`

The current item being digested.

Normally off \leq reply \leq on. Corner case of queue wrap around works because we only increment and compare for equality.

Definition at line 64 of file `lspg.c`.

5.4.5.11 `pthread_cond_t lspg_queue_cond` `[static]`

keeps the queue from overflowing

Definition at line 44 of file `lspg.c`.

5.4.5.12 `pthread_mutex_t lspg_queue_mutex` `[static]`

keep the queue from getting tangled

Definition at line 43 of file `lspg.c`.

5.4.5.13 `PostgresPollingStatusType lspg_resetPoll_response` `[static]`

Used to determine state while reconnecting.

Definition at line 70 of file `lspg.c`.

5.4.5.14 `lspg_seq_run_prep_t lspg_seq_run_prep` `[static]`

Definition at line 894 of file `lspg.c`.

5.4.5.15 `pthread_t lspg_thread` `[static]`

our worker thread

Definition at line 42 of file `lspg.c`.

5.4.5.16 `lspg_wait_for_detector_t lspg_wait_for_detector` `[static]`

Instance of the detector timing object.

Definition at line 715 of file `lspg.c`.

5.4.5.17 `struct pollfd lspgfd` `[static]`

our poll info

Definition at line 45 of file `lspg.c`.

5.4.5.18 `struct timeval lspg_time_sent now` `[static]`

used to ensure we do not inundate the db server with connection requests

Definition at line 40 of file `lspg.c`.

5.4.5.19 PGconn* q = NULL [static]

Database connector.

Definition at line 68 of file lspg.c.

5.5 lspmac.c File Reference

Routines concerned with communication with PMAC.

```
#include "pgpmac.h"
```

Data Structures

- struct [md2StatusStruct](#)
The block of memory retrieved in a status request.

Macros

- #define [LS_PMAC_STATE_RESET](#) -1
- #define [LS_PMAC_STATE_DETACHED](#) 0
- #define [LS_PMAC_STATE_IDLE](#) 1
- #define [LS_PMAC_STATE_SC](#) 2
- #define [LS_PMAC_STATE_WACK_NFR](#) 3
- #define [LS_PMAC_STATE_WACK_CC](#) 4
- #define [LS_PMAC_STATE_WACK](#) 5
- #define [LS_PMAC_STATE_GMR](#) 6
- #define [LS_PMAC_STATE_CR](#) 7
- #define [LS_PMAC_STATE_RR](#) 8
- #define [LS_PMAC_STATE_WACK_RR](#) 9
- #define [LS_PMAC_STATE_GB](#) 10
- #define [LS_PMAC_STATE_WCR](#) 11
- #define [LS_PMAC_STATE_WGB](#) 12
- #define [LSPMAC_PRESET_REGEX](#) "(.*\\.%s\\.presets)\\.[0-9]+\\.\\.(name|position)"
Regex to pick out preset name and corresponding position.
- #define [PMACPORT](#) 1025
The PMAC (only) listens on this port.
- #define [pmac_cmd_size](#) 8
PMAC command size in bytes.
- #define [VR_UPLOAD](#) 0xc0
- #define [VR_DOWNLOAD](#) 0x40
- #define [VR_PMAC_SENDLINE](#) 0xb0
- #define [VR_PMAC_GETLINE](#) 0xb1
- #define [VR_PMAC_FLUSH](#) 0xb3
- #define [VR_PMAC_GETMEM](#) 0xb4
- #define [VR_PMAC_SETMEM](#) 0xb5
- #define [VR_PMAC_SENDCTRLCHAR](#) 0xb6
- #define [VR_PMAC_SETBIT](#) 0xba
- #define [VR_PMAC_SETBITS](#) 0xbb
- #define [VR_PMAC_PORT](#) 0xbe
- #define [VR_PMAC_GETRESPONSE](#) 0xbf
- #define [VR_PMAC_READREADY](#) 0xc2

- `#define VR_CTRL_RESPONSE 0xc4`
- `#define VR_PMAC_GETBUFFER 0xc5`
- `#define VR_PMAC_WRITEBUFFER 0xc6`
- `#define VR_PMAC_WRITEERROR 0xc7`
- `#define VR_FWDOWNLOAD 0xcb`
- `#define VR_IPADDRESS 0xe0`
- `#define PMAC_MIN_CMD_TIME 20000.0`
Minimum time between commands to the pmac.
- `#define PMAC_CMD_QUEUE_LENGTH 2048`
Size of the PMAC command queue.

Typedefs

- `typedef struct md2StatusStruct md2_status_t`
The block of memory retrieved in a status request.

Functions

- `double lspmac_lut (int nlut, double *lut, double x)`
Look up table support for motor positions (think x=zoom, y=light intensity) use a lookup table to find the "counts" to move the motor to the requested position The look up table is a simple one dimensional array with the x values as even indices and the y values as odd indices.
- `double lspmac_rlut (int nlut, double *lut, double y)`
- `void hex_dump (int n, unsigned char *s)`
Prints a hex dump of the given data.
- `void cleanstr (char *s)`
Replace \r with \n in null terminated string and print result to terminal.
- `void lsConnect (char *ipaddr)`
Connect to the PMAC socket.
- `pmac_cmd_queue_t * lspmac_push_queue (pmac_cmd_queue_t *cmd)`
Put a new command on the queue.
- `pmac_cmd_queue_t * lspmac_pop_queue ()`
Remove the oldest queue item.
- `pmac_cmd_queue_t * lspmac_pop_reply ()`
Remove the next command queue item that is waiting for a reply.
- `pmac_cmd_queue_t * lspmac_send_command (int rqType, int rq, int wValue, int wIndex, int wLength, unsigned char *data, void(*responseCB)(pmac_cmd_queue_t *, int, unsigned char *), int no_reply)`
Compose a packet and send it to the PMAC.
- `void lspmac_SockFlush ()`
Reset the PMAC socket from the PMAC side.
- `void lspmac_Reset ()`
Clear the queue and put the PMAC into a known state.
- `void lspmac_Error (unsigned char *buff)`
The service routing detected an error condition.
- `void lspmac_Service (struct pollfd *evt)`
Service routine for packet coming from the PMAC.
- `void lspmac_GetShortReplyCB (pmac_cmd_queue_t *cmd, int nreceived, unsigned char *buff)`
Receive a reply that does not require multiple buffers.
- `void lspmac_SendControlReplyPrintCB (pmac_cmd_queue_t *cmd, int nreceived, unsigned char *buff)`
Receive a reply to a control character Print a "printable" version of the character to the terminal Followed by a hex dump of the response.

- void [lspmac_GetmemReplyCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, unsigned char *buff)
Service a reply to the getmem command.
- [pmac_cmd_queue_t](#) * [lspmac_SockGetmem](#) (int offset, int nbytes)
Request a chunk of memory to be returned.
- [pmac_cmd_queue_t](#) * [lspmac_SockSendline](#) (char *fmt,...)
Send a one line command.
- [pmac_cmd_queue_t](#) * [lspmac_SockSendline_nr](#) (char *fmt,...)
Send a command and ignore the response.
- [pmac_cmd_queue_t](#) * [lspmac_SockSendControlCharPrint](#) (char c)
Send a control character.
- void [lspmac_Getmem](#) ()
Request a block of double buffer memory.
- void [lspmac_bo_read](#) ([lspmac_motor_t](#) *mp)
Read the state of a binary i/o motor This is the read method for the binary i/o motor class.
- void [lspmac_dac_read](#) ([lspmac_motor_t](#) *mp)
Read a DAC motor position.
- void [lspmac_shutter_read](#) ([lspmac_motor_t](#) *mp)
Fast shutter read routine The shutter is mildly complicated in that we need to take into account the fact that the shutter can open and close again between status updates.
- void [lspmac_home1_queue](#) ([lspmac_motor_t](#) *mp)
Home the motor.
- void [lspmac_home2_queue](#) ([lspmac_motor_t](#) *mp)
Second stage of homing.
- double [lspmac_getPosition](#) ([lspmac_motor_t](#) *mp)
get the motor position (with locking)
- void [lspmac_pmacmotor_read](#) ([lspmac_motor_t](#) *mp)
Read the position and status of a normal PMAC motor.
- void [lspmac_get_status_cb](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, unsigned char *buff)
Service routing for status upate This updates positions and status information.
- void [lspmac_get_status](#) ()
Request a status update from the PMAC.
- void [lspmac_GetAllIVarsCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, unsigned char *buff)
Receive the values of all the I variables Update our Postgresql database with the results.
- void [lspmac_GetAllIVars](#) ()
Request the values of all the I variables.
- void [lspmac_GetAllMVarsCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, unsigned char *buff)
Receive the values of all the M variables Update our database with the results.
- void [lspmac_GetAllMVars](#) ()
Request the values of all the M variables.
- void [lspmac_sendcmd_nocb](#) (char *fmt,...)
Send a command that does not need to deal with the reply.
- void [lspmac_sendcmd](#) (void(*responseCB)([pmac_cmd_queue_t](#) *, int, unsigned char *), char *fmt,...)
PMAC command with call back.
- void [lspmac_next_state](#) ()
State machine logic.
- void * [lspmac_worker](#) (void *dummy)
Our lspmac worker thread.
- void [lspmac_movedac_queue](#) ([lspmac_motor_t](#) *mp, double requested_position)
Move method for dac motor objects (ie, lights)
- void [lspmac_movezoom_queue](#) ([lspmac_motor_t](#) *mp, double requested_position)
Move method for the zoom motor.

- void `lspmac_move_preset_queue` (`lspmac_motor_t` *mp, char *preset_name)
Move a given motor to one of its preset positions.
- void `lspmac_moveabs_fshut_queue` (`lspmac_motor_t` *mp, double requested_position)
Move method for the fast shutter.
- void `lspmac_moveabs_bo_queue` (`lspmac_motor_t` *mp, double requested_position)
Move method for binary i/o motor objects.
- void `lspmac_moveabs_timed_queue` (`lspmac_motor_t` *mp, double start, double delta, double time)
timed motor move
- void `lspmac_moveabs_frontlight_oo_queue` (`lspmac_motor_t` *mp, double pos)
"move" frontlight on/off
- void `lspmac_moveabs_flight_factor_queue` (`lspmac_motor_t` *mp, double pos)
- void `lspmac_moveabs_blight_factor_queue` (`lspmac_motor_t` *mp, double pos)
- void `lspmac_video_rotate` (double secs)
Special motion program to collect centering video.
- void `lspmac_move_or_jog_abs_queue` (`lspmac_motor_t` *mp, double requested_position, int use_jog)
Move method for normal stepper and servo motor objects.
- void `lspmac_move_or_jog_preset_queue` (`lspmac_motor_t` *mp, char *preset, int use_jog)
move using a preset value
- void `lspmac_moveabs_queue` (`lspmac_motor_t` *mp, double requested_position)
Use coordinate system motion program, if available, to move motor to requested position.
- void `lspmac_jogabs_queue` (`lspmac_motor_t` *mp, double requested_position)
Use jog to move motor to requested position.
- void `lspmac_moveabs_wait` (`lspmac_motor_t` *mp)
Wait for motor to finish moving.
- void `_lspmac_motor_init` (`lspmac_motor_t` *d, char *name)
Helper function for the init calls.
- `lspmac_motor_t` * `lspmac_motor_init` (`lspmac_motor_t` *d, int wy, int wx, int *posp, int *stat1p, int *stat2p, char *wtitle, char *name, void(*moveAbs)(`lspmac_motor_t` *, double))
Initialize a pmac stepper or servo motor.
- `lspmac_motor_t` * `lspmac_fshut_init` (`lspmac_motor_t` *d)
Initialize the fast shutter motor.
- `lspmac_motor_t` * `lspmac_bo_init` (`lspmac_motor_t` *d, char *name, char *write_fmt, int *read_ptr, int read_mask)
Initialize binary i/o motor.
- `lspmac_motor_t` * `lspmac_dac_init` (`lspmac_motor_t` *d, int *posp, char *mvar, char *name, void(*moveAbs)(`lspmac_motor_t` *, double))
Initialize DAC motor Note that some motors require further initialization from a database query.
- void `lspmac_soft_motor_read` (`lspmac_motor_t` *p)
Dummy routine to read a soft motor.
- `lspmac_motor_t` * `lspmac_soft_motor_init` (`lspmac_motor_t` *d, char *name, void(*moveAbs)(`lspmac_motor_t` *, double))
- `lspmac_bi_t` * `lspmac_bi_init` (`lspmac_bi_t` *d, int *ptr, int mask, char *onEvent, char *offEvent)
Initialize binary input.
- void `lspmac_init` (int ivarsflag, int mvarsflag)
Initialize this module.
- void `lspmac_cryoSwitchChanged_cb` (char *event)
- void `lspmac_scint_inPosition_cb` (char *event)
Maybe start drying off the scintillator.
- void `lspmac_backLight_up_cb` (char *event)
Turn on the backlight whenever it goes up.
- void `lspmac_backLight_down_cb` (char *event)

- Turn off the backlight whenever it goes down.*

 - void `lspmac_light_zoom_cb` (char *event)

Set the backlight intensity whenever the zoom is changed (and the backlight is up)

- void `lspmac_scint_dried_cb` (char *event)
- Turn off the dryer.*

 - void `lspmac_run` ()

find a position for a given preset name

Variables

- static int `ls_pmac_state` = `LS_PMAC_STATE_DETACHED`

Current state of the PMAC communications state machine.
- static `lsredis_obj_t` * `lspmac_md2_init`
- int `lspmac_shutter_state`

State of the shutter, used to detect changes.
- int `lspmac_shutter_has_opened`

Indicates that the shutter had opened, perhaps briefly even if the state did not change.
- pthread_mutex_t `lspmac_shutter_mutex`

Coordinates threads reading shutter status.
- pthread_cond_t `lspmac_shutter_cond`

Allows waiting for the shutter status to change.
- pthread_mutex_t `lspmac_moving_mutex`

Coordinate moving motors between threads.
- pthread_cond_t `lspmac_moving_cond`

Wait for motor(s) to finish moving condition.
- int `lspmac_moving_flags`

Flag used to implement motor moving condition.
- static int `omega_zero_search` = 0

Indicate we'd really like to know when omega crosses zero.
- static double `omega_zero_velocity` = 0

rate (cnts/sec) that omega was traveling when it crossed zero
- struct timespec `omega_zero_time`

Time we believe that omega crossed zero.
- static struct timespec `lspmac_status_time`

Time the status was read.
- static struct timespec `lspmac_status_last_time`

Time the status was read.
- static pthread_t `pmac_thread`

our thread to manage access and communication to the pmac
- pthread_mutex_t `pmac_queue_mutex`

manage access to the pmac command queue
- pthread_cond_t `pmac_queue_cond`

wait for a command to be sent to PMAC before continuing
- static struct pollfd `pmacfd`

our poll structure
- static int `getivars` = 0

flag set at initialization to send i vars to db
- static int `getmvars` = 0

flag set at initialization to send m vars to db
- `lspmac_bi_t` `lspmac_bis` [16]

- array of binary inputs*
- `int lspmac_nbis = 0`
number of active binary inputs
- `lspmac_motor_t lspmac_motors [48]`
All our motors.
- `int lspmac_nmotors = 0`
The number of motors we manage.
- `lspmac_motor_t * omega`
MD2 omega axis (the air bearing)
- `lspmac_motor_t * alignx`
Alignment stage X.
- `lspmac_motor_t * aligny`
Alignment stage Y.
- `lspmac_motor_t * alignz`
Alignment stage X.
- `lspmac_motor_t * anal`
Polaroid analyzer motor.
- `lspmac_motor_t * zoom`
Optical zoom.
- `lspmac_motor_t * apery`
Aperture Y.
- `lspmac_motor_t * aperz`
Aperture Z.
- `lspmac_motor_t * capy`
Capillary Y.
- `lspmac_motor_t * capz`
Capillary Z.
- `lspmac_motor_t * scint`
Scintillator Z.
- `lspmac_motor_t * cenx`
Centering Table X.
- `lspmac_motor_t * ceny`
Centering Table Y.
- `lspmac_motor_t * kappa`
Kappa.
- `lspmac_motor_t * phi`
Phi (not data collection axis)
- `lspmac_motor_t * fshut`
Fast shutter.
- `lspmac_motor_t * flight`
Front Light DAC.
- `lspmac_motor_t * blight`
Back Light DAC.
- `lspmac_motor_t * fscint`
Scintillator Piezo DAC.
- `lspmac_motor_t * blight_ud`
Back light Up/Down actuator.
- `lspmac_motor_t * flight_oo`
Turn front light on/off.
- `lspmac_motor_t * blight_f`
Back light scale factor.

- `lspmac_motor_t * flight_f`
Front light scale factor.
- `lspmac_motor_t * cryo`
Move the cryostream towards or away from the crystal.
- `lspmac_motor_t * dryer`
blow air on the scintillator to dry it off
- `lspmac_motor_t * fluo`
Move the fluorescence detector in/out.
- `lspmac_bi_t * cryo_switch`
that little toggle switch for the cryo
- static int `linesReceived` = 0
current number of lines received
- static unsigned char `dbmem` [64 * 1024]
double buffered memory
- static int `dbmemIn` = 0
next location
- static struct timeval
 `pmac_time_sent now`
used to ensure we do not send commands to the pmac too often. Only needed for non-DB commands.
- static `pmac_cmd_t rr_cmd`
- static `pmac_cmd_t gb_cmd`
- static `pmac_cmd_t cr_cmd`
commands to send out "readready", "getbuffer", controlresponse (initialized in main)
- static `pmac_cmd_queue_t ethCmdQueue` [PMAC_CMD_QUEUE_LENGTH]
PMAC command queue.
- static unsigned int `ethCmdOn` = 0
points to next empty PMAC command queue position
- static unsigned int `ethCmdOff` = 0
points to current command (or none if == ethCmdOn)
- static unsigned int `ethCmdReply` = 0
Used like ethCmdOff only to deal with the pmac reply to a command.
- static char * `pmac_error_strs` []
Decode the errors perhaps returned by the PMAC.
- static `md2_status_t md2_status`
Buffer for MD2 Status.
- pthread_mutex_t `md2_status_mutex`
Synchronize reading/writing status buffer.

5.5.1 Detailed Description

Routines concerned with communication with PMAC.

```
\date 2012
\author Keith Brister
\copyright All Rights Reserved
```

This is a state machine (surprise!) Lacking is support for writingbuffer, control writing and reading, as well as double buffered memory It looks like several different methods of managing PMAC communications are possible. Here is set up a queue of outgoing commands and deal completely with the result before sending the next. A full handshake of acknowledgements and "readready" is expected.

State	Description
-1	Reset the connection
0	Detached: need to connect to tcp port
1	Idle (waiting for a command to send to the pmac)
2	Send command
3	Waiting for command acknowledgement (no further response expected)
4	Waiting for control character acknowledgement (further response expected)
5	Waiting for command acknowledgement (further response expected)
6	Waiting for get memory response
7	Send controlresponse
8	Send readready
9	Waiting for acknowledgement of "readready"
10	Send readbuffer
11	Waiting for control response
12	Waiting for readbuffer response

Definition in file [lspmac.c](#).

5.5.2 Macro Definition Documentation

5.5.2.1 #define LS_PMAC_STATE_CR 7

Definition at line 45 of file lspmac.c.

5.5.2.2 #define LS_PMAC_STATE_DETACHED 0

Definition at line 38 of file lspmac.c.

5.5.2.3 #define LS_PMAC_STATE_GB 10

Definition at line 48 of file lspmac.c.

5.5.2.4 #define LS_PMAC_STATE_GMR 6

Definition at line 44 of file lspmac.c.

5.5.2.5 #define LS_PMAC_STATE_IDLE 1

Definition at line 39 of file lspmac.c.

5.5.2.6 #define LS_PMAC_STATE_RESET -1

Definition at line 37 of file lspmac.c.

5.5.2.7 #define LS_PMAC_STATE_RR 8

Definition at line 46 of file lspmac.c.

5.5.2.8 #define LS_PMAC_STATE_SC 2

Definition at line 40 of file lspmac.c.

5.5.2.9 #define LS_PMAC_STATE_WACK 5

Definition at line 43 of file lspmac.c.

5.5.2.10 #define LS_PMAC_STATE_WACK_CC 4

Definition at line 42 of file lspmac.c.

5.5.2.11 #define LS_PMAC_STATE_WACK_NFR 3

Definition at line 41 of file lspmac.c.

5.5.2.12 #define LS_PMAC_STATE_WACK_RR 9

Definition at line 47 of file lspmac.c.

5.5.2.13 #define LS_PMAC_STATE_WCR 11

Definition at line 49 of file lspmac.c.

5.5.2.14 #define LS_PMAC_STATE_WGB 12

Definition at line 50 of file lspmac.c.

5.5.2.15 #define LSPMAC_PRESET_REGEX "(.*\\.%s\\.presets)\\.([0-9]+)\\.\\.(name|position)"

Regex to pick out preset name and corresponding position.

Definition at line 114 of file lspmac.c.

5.5.2.16 #define PMAC_CMD_QUEUE_LENGTH 2048

Size of the PMAC command queue.

Definition at line 158 of file lspmac.c.

5.5.2.17 #define pmac_cmd_size 8

PMAC command size in bytes.

Definition at line 124 of file lspmac.c.

5.5.2.18 #define PMAC_MIN_CMD_TIME 20000.0

Minimum time between commands to the pmac.

Definition at line 154 of file lspmac.c.

5.5.2.19 #define PMACPORT 1025

The PMAC (only) listens on this port.
Definition at line 118 of file lspmac.c.

5.5.2.20 #define VR_CTRL_RESPONSE 0xc4

Definition at line 140 of file lspmac.c.

5.5.2.21 #define VR_DOWNLOAD 0x40

Definition at line 127 of file lspmac.c.

5.5.2.22 #define VR_FWDOWNLOAD 0xcb

Definition at line 144 of file lspmac.c.

5.5.2.23 #define VR_IPADDRESS 0xe0

Definition at line 145 of file lspmac.c.

5.5.2.24 #define VR_PMAC_FLUSH 0xb3

Definition at line 131 of file lspmac.c.

5.5.2.25 #define VR_PMAC_GETBUFFER 0xc5

Definition at line 141 of file lspmac.c.

5.5.2.26 #define VR_PMAC_GETLINE 0xb1

Definition at line 130 of file lspmac.c.

5.5.2.27 #define VR_PMAC_GETMEM 0xb4

Definition at line 132 of file lspmac.c.

5.5.2.28 #define VR_PMAC_GETRESPONSE 0xbf

Definition at line 138 of file lspmac.c.

5.5.2.29 #define VR_PMAC_PORT 0xbe

Definition at line 137 of file lspmac.c.

5.5.2.30 #define VR_PMAC_READREADY 0xc2

Definition at line 139 of file lspmac.c.

5.5.2.31 #define VR_PMAC_SENDCTRLCHAR 0xb6

Definition at line 134 of file Ispmac.c.

5.5.2.32 #define VR_PMAC_SENDLINE 0xb0

Definition at line 129 of file Ispmac.c.

5.5.2.33 #define VR_PMAC_SETBIT 0xba

Definition at line 135 of file Ispmac.c.

5.5.2.34 #define VR_PMAC_SETBITS 0xbb

Definition at line 136 of file Ispmac.c.

5.5.2.35 #define VR_PMAC_SETMEM 0xb5

Definition at line 133 of file Ispmac.c.

5.5.2.36 #define VR_PMAC_WRITEBUFFER 0xc6

Definition at line 142 of file Ispmac.c.

5.5.2.37 #define VR_PMAC_WRITEERROR 0xc7

Definition at line 143 of file Ispmac.c.

5.5.2.38 #define VR_UPLOAD 0xc0

Definition at line 126 of file Ispmac.c.

5.5.3 Typedef Documentation**5.5.3.1 typedef struct md2StatusStruct md2_status_t**

The block of memory retrieved in a status request.

5.5.4 Function Documentation**5.5.4.1 void Ispmac_motor_init (Ispmac_motor_t * d, char * name)**

Helper function for the init calls.

Definition at line 2369 of file Ispmac.c.

```

{
    Ispmac_nmotors++;

    pthread_mutex_init( &(d->mutex), NULL);
    pthread_cond_init( &(d->cond), NULL);

    d->name = strdup(name);

```

```

d->u2c          = lsredis_get_obj( "%s.u2c",
                                d->name);
d->printf_fmt   = lsredis_get_obj( "
%s.printf",
                                d->name);
d->redis_fmt     = lsredis_get_obj( "%s.format",
                                d->name);
d->unit         = lsredis_get_obj( "%s.unit",
                                d->name);
d->max_speed    = lsredis_get_obj( "
%s.max_speed",
                                d->name);
d->max_accel    = lsredis_get_obj( "
%s.max_accel",
                                d->name);
d->motor_num    = lsredis_get_obj( "
%s.motor_num",
                                d->name);
d->coord_num    = lsredis_get_obj( "
%s.coord_num",
                                d->name);
d->axis         = lsredis_get_obj( "%s.axis",
                                d->name);
d->home         = lsredis_get_obj( "%s.home",
                                d->name);
d->active       = lsredis_get_obj( "%s.active",
                                d->name);
d->active_init  = lsredis_get_obj( "
%s.active_init",
                                d->name);
d->inactive_init = lsredis_get_obj( "
%s.inactive_init",
                                d->name);

d->update_resolution = lsredis_get_obj( "
%s.update_resolution", d->name);
d->lut          = NULL;
d->nlut         = 0;
d->homing       = 0;
d->dac_mvar     = NULL;
d->actual_pos_cnts_p = NULL;
d->status1_p    = NULL;
d->status2_p    = NULL;
d->win          = NULL;
d->read         = NULL;
}

```

5.5.4.2 void cleanstr (char * s)

Replace \r with \n in null terminated string and print result to terminal.

Needed to turn PMAC messages into something printable.

Parameters

in	s	String to print to terminal.
----	---	------------------------------

Definition at line 451 of file lspmac.c.

```

{
    int i;

    pthread_mutex_lock( &ncurses_mutex);

    for( i=0; i<strlen( s); i++) {
        if( s[i] == '\r')
            wprintw( term_output, "\n");
        else
            wprintw( term_output, "%c", s[i]);
    }

    pthread_mutex_unlock( &ncurses_mutex);
}

```

5.5.4.3 void hex_dump (int n, unsigned char * s)

Prints a hex dump of the given data.

Used to debug packet data.

Parameters

in	<i>n</i>	Number of bytes passed in s
in	<i>s</i>	Data to dump

Definition at line 423 of file lspmac.c.

```

{

int i;          // row counter
int j;          // column counter

pthread_mutex_lock( &ncurses_mutex);

for( i=0; n > 0; i++) {
    for( j=0; j<16 && n > 0; j++) {
        if( j==8)
            wprintw( term_output, "  ");
        wprintw( term_output, " %02x", *(s + 16*i + j));
        n--;
    }
    wprintw( term_output, "\n");
}
wprintw( term_output, "\n");

pthread_mutex_unlock( &ncurses_mutex);
}

```

5.5.4.4 void lsConnect (char * ipaddr)

Connect to the PMAC socket.

Establish or reestablish communications.

Parameters

in	<i>ipaddr</i>	String representation of the IP address (dot quad or FQN)
----	---------------	---

Definition at line 472 of file lspmac.c.

```

{

int psock;          // our socket: value stored in pmacfda.fd
int err;            // error code from some system calls
struct sockaddr_in *addrP; // our address structure to connect to
struct addrinfo ai_hints; // required for getaddrinfo
struct addrinfo *ai_resultP; // linked list of address structures (we'll
    always pick the first)

pmacfd.fd = -1;
pmacfd.events = 0;

// Initial buffer(s)
memset( &ai_hints, 0, sizeof( ai_hints));

ai_hints.ai_family = AF_INET;
ai_hints.ai_socktype = SOCK_STREAM;

//
// get address
//
err = getaddrinfo( ipaddr, NULL, &ai_hints, &ai_resultP);
if( err != 0) {

    lslogging_log_message( "Could not find address: %s",
        gai_strerror( err));

    return;
}

addrP = (struct sockaddr_in *)ai_resultP->ai_addr;
addrP->sin_port = htons( PMACPORT);

psock = socket( PF_INET, SOCK_STREAM, 0);
if( psock == -1) {

```

```

    lslogging_log_message( "Could not create socket");
    return;
}

err = connect( psock, (const struct sockaddr *)addrP, sizeof( *addrP));
if( err != 0) {
    lslogging_log_message( "Could not connect socket: %s",
        strerror( errno));
    return;
}

ls_pmac_state = LS_PMAC_STATE_IDLE;
pmacfd.fd      = psock;
pmacfd.events  = POLLIN;
}

```

5.5.4.5 void lspmac_backLight_down_cb (char * event)

Turn off the backlight whenever it goes down.

Parameters

<i>event</i>	Name of the event that called us
--------------	----------------------------------

Definition at line 2671 of file lspmac.c.

```

{
    blight->moveAbs( blight, 0.0);
}

```

5.5.4.6 void lspmac_backLight_up_cb (char * event)

Turn on the backlight whenever it goes up.

Parameters

<i>event</i>	Name of the event that called us
--------------	----------------------------------

Definition at line 2662 of file lspmac.c.

```

{
    int z;

    blight->moveAbs( blight, lspmac_getPosition
        ( zoom));
}

```

5.5.4.7 lspmac_bi_t* lspmac_bi_init(lspmac_bi_t * d, int * ptr, int mask, char * onEvent, char * offEvent)

Initialize binary input.

Definition at line 2514 of file lspmac.c.

```

{
    lspmac_nbis++;
    pthread_mutex_init( &(d->mutex), NULL);
    d->ptr      = ptr;
    d->mask     = mask;
    d->changeEventOn = strdup( onEvent);
    d->changeEventOff = strdup( offEvent);
    d->first_time = 1;
}

```

5.5.4.8 `lspmac_motor_t* lspmac_bo_init (lspmac_motor_t * d, char * name, char * write_fmt, int * read_ptr, int read_mask)`

Initialize binary i/o motor.

Parameters

in	<i>d</i>	Our uninitialized motor object
in	<i>name</i>	Name of motor to coordinate with DB
in	<i>write_fmt</i>	Format string used to generate PMAC command to move motor
in	<i>read_ptr</i>	Pointer to byte in md2_status to find position
in	<i>read_mask</i>	Bitmask to find position in *read_ptr

Definition at line 2450 of file `lspmac.c`.

```

{
    _lspmac_motor_init( d, name);

    d->moveAbs      = lspmac_moveabs_bo_queue;
    d->read          = lspmac_bo_read;
    d->write_fmt     = strdup( write_fmt);
    d->read_ptr      = read_ptr;
    d->read_mask     = read_mask;

    return d;
}

```

5.5.4.9 `void lspmac_bo_read (lspmac_motor_t * mp)`

Read the state of a binary i/o motor This is the read method for the binary i/o motor class.

Parameters

in	<i>mp</i>	The motor
----	-----------	-----------

Definition at line 1017 of file `lspmac.c`.

```

{
    char s[512];
    int pos, changed;

    pthread_mutex_lock( &(mp->mutex));

    pos = (*(mp->read_ptr) & mp->read_mask) == 0 ? 0 : 1;

    changed = pos != mp->position;
    mp->position = pos;

    // Not sure what kind of status makes sense to report
    mp->statuss[0] = 0;
    pthread_mutex_unlock( &(mp->mutex));

    if( changed)
        lsevents_send_event( "%s %d", mp->name, pos);
}

```

5.5.4.10 `void lspmac_cryoSwitchChanged_cb (char * event)`

Definition at line 2624 of file `lspmac.c`.

```

{
    int pos;

    pthread_mutex_lock( &(cryo->mutex));
    pos = cryo->position;
}

```

```

pthread_mutex_unlock( &(cryo->mutex));

cryo->moveAbs( cryo, pos ? 0.0 : 1.0);
}

```

5.5.4.11 `lspmac_motor_t* lspmac_dac_init(lspmac_motor_t * d, int * posp, char * mvar, char * name, void (*)(lspmac_motor_t *, double) moveAbs)`

Initialize DAC motor Note that some motors require further initialization from a database query.

For this reason this initialization code must be run before the database queue is allowed to be processed.

Parameters

out	<i>d</i>	Returns the (almost) initialized motor object [in,out] unitinitialized motor
in	<i>posp</i>	Location of current position
in	<i>mvar</i>	M variable, ie, "M1200"
in	<i>name</i>	name to coordinate with DB
in	<i>moveAbs</i>	Method to use to move this motor

Definition at line 2476 of file `lspmac.c`.

```

{

_lspmac_motor_init( d, name);
d->moveAbs          = moveAbs;
d->read             = lspmac_dac_read;
d->actual_pos_cnts_p = posp;
d->dac_mvar         = strdup(mvar);

return d;
}

```

5.5.4.12 `void lspmac_dac_read(lspmac_motor_t * mp)`

Read a DAC motor position.

Parameters

in	<i>mp</i>	The motor
----	-----------	-----------

Definition at line 1040 of file `lspmac.c`.

```

{

int pos;
double u2c;

pthread_mutex_lock( &(mp->mutex));
mp->actual_pos_cnts = *mp->actual_pos_cnts_p;
u2c = lsredis_getd( mp->u2c);

if( mp->nlut >0 && mp->lut != NULL) {
    if( u2c == 0.0)
        u2c = 1.0;
    mp->position = lspmac_rlut( mp->nlut, mp->lut, mp
        ->actual_pos_cnts/u2c);
} else {
    if( u2c != 0.0) {
        mp->position = mp->actual_pos_cnts / u2c;
    } else {
        mp->position = mp->actual_pos_cnts;
    }
}

// Not sure what kind of status makes sense to report
mp->status[0] = 0;

pthread_mutex_unlock( &(mp->mutex));
}

```


5.5.4.13 void lspmac_Error (unsigned char * buff)

The service routing detected an error condition.

Scan the response buffer for an error code and print it out.

Parameters

in	<i>buff</i>	Buffer returned by PMAC perhaps containing a NULL terminated message.
----	-------------	---

Definition at line 669 of file lspmac.c.

```

    {
        int err;
        //
        // assume buff points to a 1400 byte array of stuff read from the pmac
        //

        if( buff[0] == 7 && buff[1] == 'E' && buff[2] == 'R' && buff[3] == 'R' ) {
            buff[7] = 0; // For null termination
            err = atoi( &(buff[4]));
            if( err > 0 && err < 20 ) {
                lslogging_log_message( pmac_error_strs
                    [err]);

                pthread_mutex_lock( &ncurses_mutex);
                wprintw( term_output, "\n%s\n", pmac_error_strs
                    [err]);
                wnoutrefresh( term_output);
                wnoutrefresh( term_input);
                douupdate();
                pthread_mutex_unlock( &ncurses_mutex);
            }
        }
        lspmac_Reset();
    }

```

5.5.4.14 lspmac_motor_t* lspmac_fshut_init (lspmac_motor_t * d)

Initialize the fast shutter motor.

Parameters

in	<i>d</i>	Our uninitialized motor object
----	----------	--------------------------------

Definition at line 2434 of file lspmac.c.

```

    {
        _lspmac_motor_init( d, "fastShutter");

        d->moveAbs          = lspmac_moveabs_fshut_queue
        ;
        d->read              = lspmac_shutter_read;

        return d;
    }

```

5.5.4.15 void lspmac_get_status ()

Request a status update from the PMAC.

Definition at line 1619 of file lspmac.c.

```

    {
        lspmac_send_command( VR_UPLOAD, VR_PMAC_GETMEM
            , 0x400, 0, sizeof(md2_status_t), NULL, lspmac_get_status_cb
            , 0);
    }

```

5.5.4.16 void lspmac_get_status_cb (pmac_cmd_queue_t * cmd, int nreceived, unsigned char * buff)

Service routing for status update This updates positions and status information.

Parameters

in	<i>cmd</i>	The command that generated this reply
in	<i>nreceived</i>	Number of bytes received
in	<i>buff</i>	The Big Byte Buffer

Definition at line 1447 of file lspmac.c.

```

{
    static int cnt = 0;
    static char s[256];
    static struct timeval ts1, ts2;

    char *sp;
    int i, pos;
    lspmac_motor_t *mp;
    lspmac_bi_t *bp;

    clock_gettime( CLOCK_REALTIME, &lspmac_status_time);

    if( cnt == 0) {
        gettimeofday( &ts1, NULL);
    }

    pthread_mutex_lock( &md2_status_mutex);
    memcpy( &md2_status, buff, sizeof(md2_status));
    pthread_mutex_unlock( &md2_status_mutex);

    //
    // track the coordinate system moving flags
    //
    pthread_mutex_lock( &lspmac_moving_mutex);
    if( md2_status.moving_flags != lspmac_moving_flags
        ) {
        lslogging_log_message( "lspmac_get_status_cb: new
            moving flag: %0x", md2_status.moving_flags);
        lspmac_moving_flags = md2_status.moving_flags
            ;
        pthread_cond_signal( &lspmac_moving_cond);
    }
    pthread_mutex_unlock( &lspmac_moving_mutex);

    //
    // Read the motor positions
    //
    for( i=0; i<lspmac_nmotors; i++) {
        lspmac_motors[i].read(&(lspmac_motors[i]));
    }

    //
    // Read the binary inputs and perhaps send an event
    //
    for( i=0; i<lspmac_nbis; i++) {
        bp = &(lspmac_bis[i]);

        pthread_mutex_lock( &(bp->mutex));

        pos = (*(bp->ptr) & bp->mask) == 0 ? 0 : 1;

        if( bp->first_time) {
            bp->first_time = 0;
            if( pos==1 && bp->changeEventOn != NULL && bp->changeEventOn
                [0] != 0)
                lsevents_send_event( lspmac_bis[i].
                    changeEventOn);
            if( pos==0 && bp->changeEventOff != NULL && bp->
                changeEventOff[0] != 0)
                lsevents_send_event( lspmac_bis[i].
                    changeEventOff);
        } else {
            if( pos != bp->previous) {
                if( pos==1 && bp->changeEventOn != NULL && bp->
                    changeEventOn[0] != 0)
                    lsevents_send_event( lspmac_bis[i].
                        changeEventOn);
                if( pos==0 && bp->changeEventOff != NULL && bp->

```

```

        changeEventOff[0] != 0)
            lsevents_send_event( lspmac_bis[i].
        changeEventOff);
    }
}
bp->previous = pos;
pthread_mutex_unlock( &(bp->mutex));
}

pthread_mutex_lock( &ncurses_mutex);

// acc11c_1
// mask bit
// 0x01 0   Air pressure OK
// 0x02 1   Air bearing OK
// 0x04 2   Cryo switch
// 0x08 3
// 0x10 4
// 0x20 5
// 0x40 6   Cryo is back

//
// acc11c_2
// mask bit
// 0x01 0   Fluor Dector back
// 0x02 1   Sample Detected
// 0x04 2
// 0x08 3
// 0x10 4
// 0x20 5   Etel Ready
// 0x40 6   Etel On
// 0x80 7   Etel Init OK

if( md2_status.acc11c_2 & 0x01)
    mvwprintw( term_status2, 3, 10, "%s", -8, "Fluor Out");
else
    mvwprintw( term_status2, 3, 10, "%s", -8, "Fluor In");

if( md2_status.acc11c_5 & 0x08)
    mvwprintw( term_status2, 4, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Dryer On");
else
    mvwprintw( term_status2, 4, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Dryer Off");

if( md2_status.acc11c_2 & 0x02)
    mvwprintw( term_status2, 2, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Cap Dected");
else
    mvwprintw( term_status2, 2, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Cap Not Dected");
wnoutrefresh( term_status2);

// acc11c_3
// mask bit
// 0x01 0   Minikappa OK
// 0x02 1
// 0x04 2
// 0x08 3   Arm Parked

// acc11c_5
// mask bit
// 0x01 0   Mag Off
// 0x02 1   Condenser Out
// 0x04 2   Cryo Back
// 0x08 3   Dryer On
// 0x10 4   FluoDet Out
// 0x20 5
// 0x40 6   1=SmartMag, 0=Permanent Mag
//

if( md2_status.acc11c_5 & 0x04)
    mvwprintw( term_status2, 3, 1, "%s", -8, "Cryo Out");
else
    mvwprintw( term_status2, 3, 1, "%s", -8, "Cryo In ");

// acc11c_6
// mask bit
// 0x0080 7   Etel Enable
// 0x0100 8   Fast Shutter Enable
// 0x0200 9   Fast Shutter Manual Enable
// 0x0400 10  Fast Shutter On

if( md2_status.acc11c_5 & 0x02)

```

```

    mvwprintw( term_status, 3, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Backlight Up");
else
    mvwprintw( term_status, 3, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
-2), "Backlight Down");

mvwprintw( term_status, 4, 1, "Front: %u",
    LS_DISPLAY_WINDOW_WIDTH-2-8, (int)flight->position);
mvwprintw( term_status, 5, 1, "Back: %u", LS_DISPLAY_WINDOW_WIDTH
-2-7, (int)blight->position);
mvwprintw( term_status, 6, 1, "Piezo: %u",
    LS_DISPLAY_WINDOW_WIDTH-2-8, (int)fscint->position);
wnoutrefresh( term_status);

wnoutrefresh( term_input);
doupdate();
pthread_mutex_unlock( &ncurses_mutex);

/*
if( ++cnt % 1000 == 0) {
    gettimeofday( &ts2, NULL);

    lslogging_log_message( "Refresh Rate: %0.1f Hz", 1000000.*(cnt)/(ts2.tv_sec
*1000000 + ts2.tv_usec - ts1.tv_sec*1000000 - ts1.tv_usec));

    cnt = 0;
}
*/
}

```

5.5.4.17 void lspmac.GetAllIVars ()

Request the values of all the I variables.

Definition at line 1644 of file lspmac.c.

```

{
    static char *cmds = "I0..8191";
    lspmac_send_command( VR_DOWNLOAD,
        VR_PMAC_SENDLINE, 0, 0, strlen( cmds), cmds,
        lspmac_GetAllIVarsCB, 0);
}

```

5.5.4.18 void lspmac.GetAllIVarsCB (pmac_cmd_queue_t * cmd, int nreceived, unsigned char * buff)

Receive the values of all the I variables Update our Postgresql database with the results.

Parameters

in	<i>cmd</i>	The command that gave this response
in	<i>nreceived</i>	Number of bytes received
in	<i>buff</i>	The byte buffer

Definition at line 1627 of file lspmac.c.

```

{
    static char qs[LS_PG_QUERY_STRING_LENGTH];
    char *sp;
    int i;
    for( i=0, sp=strtok(buff, "\r"); sp != NULL; sp=strtok( NULL, "\r"), i++) {
        snprintf( qs, sizeof( qs)-1, "SELECT pmac.md2_ivar_set( %d, '%s')", i, sp);
        qs[sizeof( qs)-1]=0;
        lspg_query_push( NULL, qs);
    }
}

```

5.5.4.19 void lspmac.GetAllMVars ()

Request the values of all the M variables.

Definition at line 1669 of file lspmac.c.

```

    {
static char *cmds = "M0..8191->";
lspmac_send_command( VR_DOWNLOAD,
VR_PMAC_SENDLINE, 0, 0, strlen( cmds), cmds,
lspmac_GetAllMVarsCB, 0);
}

```

5.5.4.20 void lspmac.GetAllMVarsCB (pmac_cmd_queue_t * cmd, int nreceived, unsigned char * buff)

Receive the values of all the M variables Update our database with the results.

Parameters

in	<i>cmd</i>	The command that started this
in	<i>nreceived</i>	Number of bytes received
in	<i>buff</i>	Our byte buffer

Definition at line 1652 of file lspmac.c.

```

    {
static char qs[LS_PG_QUERY_STRING_LENGTH];
char *sp;
int i;
for( i=0, sp=strtok(buff, "\r"); sp != NULL; sp=strtok( NULL, "\r"), i++) {
snprintf( qs, sizeof( qs)-1, "SELECT pmac.md2_mvar_set( %d, '%s')", i, sp);
qs[sizeof( qs)-1]=0;
lspg_query_push( NULL, qs);
}
}

```

5.5.4.21 void lspmac.Getmem ()

Request a block of double buffer memory.

Definition at line 1008 of file lspmac.c.

```

    {
int nbytes;
nbytes = (dbmemIn + 1400 > sizeof( dbmem)) ? sizeof( dbmem)
- dbmemIn : 1400;
lspmac_SockGetmem( dbmemIn, nbytes);
}

```

5.5.4.22 void lspmac.GetmemReplyCB (pmac_cmd_queue_t * cmd, int nreceived, unsigned char * buff)

Service a reply to the getmem command.

Not currently used.

Parameters

	<i>cmd</i>	Queue item this is a reply to
	<i>nreceived</i>	Number of bytes received
	<i>buff</i>	Buffer of bytes recieved

Definition at line 939 of file lspmac.c.

```

{

```

```

memcpy( &(dbmem[ntohs(cmd->pcmd.wValue)]), buff, nreceived);

dbmemIn += nreceived;
if( dbmemIn >= sizeof( dbmem)) {
    dbmemIn = 0;
}
}

```

5.5.4.23 double lspmac_getPosition (lspmac_motor_t * mp)

get the motor position (with locking)

Parameters

<i>mp</i>	the motor object
-----------	------------------

Definition at line 1236 of file lspmac.c.

```

{
double rtn;
pthread_mutex_lock( &(mp->mutex));
rtn = mp->position;
pthread_mutex_unlock( &(mp->mutex));
return rtn;
}

```

5.5.4.24 void lspmac_GetShortReplyCB (pmac_cmd_queue_t * cmd, int nreceived, unsigned char * buff)

Receive a reply that does not require multiple buffers.

Parameters

in	<i>cmd</i>	Queue item this is a reply to
in	<i>nreceived</i>	Number of bytes received
in	<i>buff</i>	The buffer of bytes

Definition at line 881 of file lspmac.c.

```

{
char *sp;          // pointer to the command this is a reply to

if( nreceived < 1400)
    buff[nreceived]=0;

sp = (char *) (cmd->pcmd.bData);

if( *buff == 0) {
    pthread_mutex_lock( &ncurses_mutex);
    wprintw( term_output, "%s\n", sp);
    pthread_mutex_unlock( &ncurses_mutex);
} else {
    pthread_mutex_lock( &ncurses_mutex);
    wprintw( term_output, "%s: ", sp);
    pthread_mutex_unlock( &ncurses_mutex);
    cleanstr( buff);
}
wnoutrefresh( term_output);
wnoutrefresh( term_input);
doupdate();

memset( cmd->pcmd.bData, 0, sizeof( cmd->pcmd.bData));
}

```

5.5.4.25 void lspmac_home1_queue (lspmac_motor_t * mp)

Home the motor.

Parameters

in	<i>mp</i>	motor we are concerned about
----	-----------	------------------------------

Definition at line 1111 of file lspmac.c.

```

{
    char openloops[32];
    char *sp;
    int i;
    int motor_num;
    int coord_num;
    char **home;

    pthread_mutex_lock( &(mp->mutex));

    motor_num = lsredis_get1( mp->motor_num);
    coord_num = lsredis_get1( mp->coord_num);
    home      = lsredis_get_string_array( mp->home);

    // Each of the motors should have this defined
    // but let's not seg fault if home is missing
    //
    if( home == NULL || *home == NULL) {
        //
        // Note we are already initialized
        // so if we are here there is something wrong.
        //
        lslogging_log_message( "lspmac_home1_queue: null or
            empty home strings for motor %s", mp->name);
        pthread_mutex_unlock( &(mp->mutex));
        return;
    }

    // We've already been called. Don't home again until
    // we're finish with the last time.
    //
    if( mp->homing) {
        pthread_mutex_unlock( &(mp->mutex));
        return;
    }

    //
    // Don't go on if any other motors in this coordinate system are homing.
    // It's possible to write the homing program to home all the motors in the
    // coordinate
    // system.
    //
    if( coord_num > 0) {
        for( i=0; i<lspmac_nmotors; i++) {
            if( &(lspmac_motors[i]) == mp)
                continue;
            if( lsredis_get1(lspmac_motors[i].coord_num) ==
                coord_num) {
                if( lspmac_motors[i].homing) {
                    pthread_mutex_unlock( &(mp->mutex));
                    return;
                }
            }
        }
    }
    mp->homing = 1;

    // This opens the control loop.
    // The status routine should notice this and the fact that
    // the homing flag is set and call on the home2 routine
    //
    // Only send the open loop command if we are not in
    // open loop mode already. This test might prevent a race condition
    // where we've already moved the home2 routine (and queue the homing program
    // motion)
    // before the open loop command is dequeued and acted on.
    //
    if( ~(mp->status1) & 0x040000) {
        snprintf( openloops, sizeof(openloops)-1, "%d$*", motor_num);
        openloops[sizeof(openloops)-1] = 0;
        lspmac_SockSendline( openloops);
    }

    pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.26 void lspmac_home2_queue (lspmac_motor_t * mp)

Second stage of homing.

Parameters

in	<i>mp</i>	motor we are concerned about
----	-----------	------------------------------

Definition at line 1189 of file lspmac.c.

```

{

char **spp;
char **home;

//
// At this point we are in open loop.
// Run the motor specific commands
//

pthread_mutex_lock( &(mp->mutex));

home = lsredis_get_string_array( mp->home);

//
// We don't have any motors that have a null home text array so
// there is currently no need to worry about this case other than
// not to seg fault
//
// Also, Only go on if the first homing phase has been started
//
if( home == NULL || mp->homing != 1) {
    pthread_mutex_unlock( &(mp->mutex));
    return;
}

for( spp = home; *spp != NULL; spp++) {

    pthread_mutex_lock( &ncurses_mutex);
    wprintw( term_output, "home2 is queuing '%s'\n", *spp);
    wnoutrefresh( term_output);
    doupdate();
    pthread_mutex_unlock( &ncurses_mutex);

    lspmac_SockSendline( *spp);
}

mp->homing = 2;
pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.27 void lspmac_init (int ivarsflag, int mvarsflag)

Initialize this module.

Parameters

in	<i>ivarsflag</i>	Set global flag to harvest i variables
in	<i>mvarsflag</i>	Set global flag to harvest m variables

Definition at line 2528 of file lspmac.c.

```

{
md2_status_t *p;

// Set our global harvest flags
getivars = ivarsflag;
getmvars = mvarsflag;

// All important status mutex
pthread_mutex_init( &md2_status_mutex, NULL);

//

```



```

// Get the MD2 initialization strings
//
lspmac_md2_init = lsredis_get_obj( "
    md2_pmac.init");

//
// Initialize the motor objects
//

p = &md2_status;

omega = lspmac_motor_init( &(lspmac_motors
    [ 0]), 0, 0, &p->omega_act_pos, &p->omega_status_1
    , &p->omega_status_2, "Omega #1 &1 A", "omega",
    lspmac_moveabs_queue);
alignx = lspmac_motor_init( &(lspmac_motors
    [ 1]), 0, 1, &p->alignx_act_pos, &p->alignx_status_1
    , &p->alignx_status_2, "Align X #2 &3 X", "align.x",
    lspmac_moveabs_queue);
aligny = lspmac_motor_init( &(lspmac_motors
    [ 2]), 0, 2, &p->aligny_act_pos, &p->aligny_status_1
    , &p->aligny_status_2, "Align Y #3 &3 Y", "align.y",
    lspmac_moveabs_queue);
alignz = lspmac_motor_init( &(lspmac_motors
    [ 3]), 0, 3, &p->alignz_act_pos, &p->alignz_status_1
    , &p->alignz_status_2, "Align Z #4 &3 Z", "align.z",
    lspmac_moveabs_queue);
anal = lspmac_motor_init( &(lspmac_motors
    [ 4]), 0, 4, &p->analyzer_act_pos, &p->analyzer_status_1
    , &p->analyzer_status_2, "Anal #5", "lightPolar",
    lspmac_moveabs_queue);
zoom = lspmac_motor_init( &(lspmac_motors
    [ 5]), 1, 0, &p->zoom_act_pos, &p->zoom_status_1
    , &p->zoom_status_2, "Zoom #6 &4 Z", "cam.zoom",
    lspmac_movezoom_queue);
apery = lspmac_motor_init( &(lspmac_motors
    [ 6]), 1, 1, &p->aperturey_act_pos, &p->aperturey_status_1
    , &p->aperturey_status_2, "Aper Y #7 &5 Y", "appy",
    lspmac_moveabs_queue);
aperz = lspmac_motor_init( &(lspmac_motors
    [ 7]), 1, 2, &p->aperturez_act_pos, &p->aperturez_status_1
    , &p->aperturez_status_2, "Aper Z #8 &5 Z", "appz",
    lspmac_moveabs_queue);
capy = lspmac_motor_init( &(lspmac_motors
    [ 8]), 1, 3, &p->capy_act_pos, &p->capy_status_1
    , &p->capy_status_2, "Cap Y #9 &5 U", "capy",
    lspmac_moveabs_queue);
capz = lspmac_motor_init( &(lspmac_motors
    [ 9]), 1, 4, &p->capz_act_pos, &p->capz_status_1
    , &p->capz_status_2, "Cap Z #10 &5 V", "capz",
    lspmac_moveabs_queue);
scint = lspmac_motor_init( &(lspmac_motors
    [10]), 2, 0, &p->scint_act_pos, &p->scint_status_1
    , &p->scint_status_2, "Scin Z #11 &5 W", "scint",
    lspmac_moveabs_queue);
cenx = lspmac_motor_init( &(lspmac_motors
    [11]), 2, 1, &p->centerx_act_pos, &p->centerx_status_1
    , &p->centerx_status_2, "Cen X #17 &2 X", "centering.x",
    lspmac_moveabs_queue);
ceny = lspmac_motor_init( &(lspmac_motors
    [12]), 2, 2, &p->centery_act_pos, &p->centery_status_1
    , &p->centery_status_2, "Cen Y #18 &2 Y", "centering.y",
    lspmac_moveabs_queue);
kappa = lspmac_motor_init( &(lspmac_motors
    [13]), 2, 3, &p->kappa_act_pos, &p->kappa_status_1
    , &p->kappa_status_2, "Kappa #19 &7 X", "kappa",
    lspmac_moveabs_queue);
phi = lspmac_motor_init( &(lspmac_motors[
    14]), 2, 4, &p->phi_act_pos, &p->phi_status_1
    , &p->phi_status_2, "Phi #20 &7 Y", "phi",
    lspmac_moveabs_queue);

fshut = lspmac_fshut_init( &(lspmac_motors
    [15]));
flight = lspmac_dac_init( &(lspmac_motors[1
    6]), &p->front_dac, "M1200", "frontLight.intensity",
    lspmac_movedac_queue);
blight = lspmac_dac_init( &(lspmac_motors[1
    7]), &p->back_dac, "M1201", "backLight.intensity",
    lspmac_movedac_queue);
fscint = lspmac_dac_init( &(lspmac_motors[1
    8]), &p->scint_piezo, "M1203", "scint.focus",
    lspmac_movedac_queue);

blight_ud = lspmac_bo_init( &(lspmac_motors
    [19]), "backLight", "M1101=%d", &(md2_status.accllc_5), 0x02)
;

```

```

cryo      = lspmac_bo_init( &(lspmac_motors[20
    ]), "cryo",          "M1102=%d", &(md2_status.acc11c_5), 0x04);
dryer     = lspmac_bo_init( &(lspmac_motors[2
    ]), "dryer",        "M1103=%d", &(md2_status.acc11c_5), 0x08);
fluo      = lspmac_bo_init( &(lspmac_motors[22
    ]), "fluo",         "M1008=%d", &(md2_status.acc11c_2), 0x01);
flight_oo = lspmac_soft_motor_init( &(
    lspmac_motors[23]), "frontLight",
    lspmac_moveabs_frontlight_oo_queue);
blight_f  = lspmac_soft_motor_init( &(
    lspmac_motors[24]), "backLight.factor",
    lspmac_moveabs_blight_factor_queue);
flight_f  = lspmac_soft_motor_init( &(
    lspmac_motors[25]), "frontLight.factor",
    lspmac_moveabs_flight_factor_queue);

cryo_switch = lspmac_bi_init( &(lspmac_bis
    [0]), &(md2_status.acc11c_1), 0x04, "CryoSwitchChanged", "
    CryoSwitchChanged");

//
// Initialize several commands that get called, perhaps, alot
//
rr_cmd.RequestType = VR_UPLOAD;
rr_cmd.Request     = VR_PMAC_READREADY;
rr_cmd.wValue      = 0;
rr_cmd.wIndex      = 0;
rr_cmd.wLength     = htons(2);
memset( rr_cmd.bData, 0, sizeof(rr_cmd.bData));

gb_cmd.RequestType = VR_UPLOAD;
gb_cmd.Request     = VR_PMAC_GETBUFFER;
gb_cmd.wValue      = 0;
gb_cmd.wIndex      = 0;
gb_cmd.wLength     = htons(1400);
memset( gb_cmd.bData, 0, sizeof(gb_cmd.bData));

cr_cmd.RequestType = VR_UPLOAD;
cr_cmd.Request     = VR_CTRL_RESPONSE;
cr_cmd.wValue      = 0;
cr_cmd.wIndex      = 0;
cr_cmd.wLength     = htons(1400);
memset( cr_cmd.bData, 0, sizeof(cr_cmd.bData));

//
// Initialize some mutexs and conditions
//

pthread_mutex_init( &pmac_queue_mutex, NULL);
pthread_cond_init( &pmac_queue_cond, NULL);

lspmac_shutter_state = 0; //
    assume the shutter is now closed: not a big deal if we are wrong
pthread_mutex_init( &lspmac_shutter_mutex, NULL);
pthread_cond_init( &lspmac_shutter_cond, NULL);
pmacfd.fd = -1;

pthread_mutex_init( &lspmac_moving_mutex, NULL);
pthread_cond_init( &lspmac_moving_cond, NULL);
}

```

5.5.4.28 void lspmac_jogabs_queue (lspmac_motor_t * mp, double requested_position)

Use jog to move motor to requested position.

Parameters

in	<i>mp</i>	The motor to move
in	<i>requested_ - position</i>	Where to move it

Definition at line 2291 of file lspmac.c.

```

{
    lspmac_move_or_jog_abs_queue( mp,
        requested_position, 1);
}

```

5.5.4.29 void lspmac_light_zoom_cb (char * event)

Set the backlight intensity whenever the zoom is changed (and the backlight is up)

Parameters

<i>event</i>	Name of the event that called us
--------------	----------------------------------

Definition at line 2678 of file lspmac.c.

```

{
double z;

z = lspmac_getPosition( zoom);
if( lspmac_getPosition( flight_oo) != 0.0) {
    flight->moveAbs( flight, z);
} else {
    flight->moveAbs( flight, 0.0);
}
if( lspmac_getPosition( blight_ud) != 0.0) {
    blight->moveAbs( blight, z);
} else {
    blight->moveAbs( blight, 0.0);
}
}
}

```

5.5.4.30 double lspmac_lut (int nlut, double * lut, double x)

Look up table support for motor positions (think x=zoom, y=light intensity) use a lookup table to find the "counts" to move the motor to the requested position The look up table is a simple one dimensional array with the x values as even indicies and the y values as odd indices.

Returns: y value

Parameters

<i>in</i>	<i>nlut</i>	number of entries in lookup table
<i>in</i>	<i>lut</i>	The lookup table: even indicies are the x values, odd are the y's
<i>in</i>	<i>x</i>	The x value we are looking up.

Definition at line 310 of file lspmac.c.

```

{
int i, foundone;
double m;
double y1, y2, x1, x2, y;

foundone = 0;
if( lut != NULL && nlut > 1) {
    for( i=0; i < 2*nlut; i += 2) {
        x1 = lut[i];
        y1 = lut[i+1];
        if( i < 2*nlut - 2) {
            x2 = lut[i+2];
            y2 = lut[i+3];
        }

        //
        // First one too big? Use the y value of the first element
        //
        if( i == 0 && x1 > x) {
            y = y1;
            foundone = 1;
            break;
        }

        //
        // Look for equality
        //
        if( x1 == x) {
            y = y1;
            foundone = 1;
        }
    }
}

```

```

        break;
    }

    //
    // Maybe interpolate
    //
    if( (i < 2*nlut-2) && x < x2) {
        m = (y2 - y1) / (x2 - x1);
        y = m*(x - x1) + y1;
        foundone = 1;
        break;
    }
}
if( foundone == 0) {
    // must be bigger than the last entry
    //
    //
    y = lut[2*(nlut-1) + 1];
}
return y;
}
return 0.0;
}

```

5.5.4.31 `lspmac_motor_t* lspmac_motor_init (lspmac_motor_t * d, int wy, int wx, int * posp, int * stat1p, int * stat2p, char * wtitle, char * name, void(*) (lspmac_motor_t *, double) moveAbs)`

Initialize a pmac stepper or servo motor.

Parameters

in, out	<i>d</i>	An uninitialized motor object
in	<i>wy</i>	Curses status window row index
in	<i>wx</i>	Curses status window column index
in	<i>posp</i>	Pointer to position status
in	<i>stat1p</i>	Pointer to 1st status word
in	<i>stat2p</i>	Pointer to 2nd status word
in	<i>wtitle</i>	Title for this motor (to display)
in	<i>name</i>	This motor's name
in	<i>moveAbs</i>	Method to use to move this motor

Definition at line 2405 of file `lspmac.c`.

```

{

    _lspmac_motor_init( d, name);

    d->moveAbs          = moveAbs;
    d->read              = lspmac_pmacmotor_read;
    d->actual_pos_cnts_p = posp;
    d->status1_p         = stat1p;
    d->status2_p         = stat2p;
    d->win = newwin( LS_DISPLAY_WINDOW_HEIGHT,
        LS_DISPLAY_WINDOW_WIDTH, wy*LS_DISPLAY_WINDOW_HEIGHT,
        wx*LS_DISPLAY_WINDOW_WIDTH);
    box( d->win, 0, 0);
    mvwprintw( d->win, 1, 1, "%s", wtitle);
    wnoutrefresh( d->win);

    return d;
}

```

5.5.4.32 `void lspmac_move_or_jog_abs_queue (lspmac_motor_t * mp, double requested_position, int use_jog)`

Move method for normal stepper and servo motor objects.

< buffer to send to pmac

< coordinate system bit

- < the requested position in units of "counts"
- < motor and coordinate system;
- < our axis

Parameters

in	<i>mp</i>	The motor to move
in	<i>requested_position</i>	Where to move it
in	<i>use_jog</i>	1 to force jog, 0 for motion prog

Definition at line 2143 of file lspmac.c.

```

{
    char s[512];
    int q100;
    int requested_pos_cnts;
    int coord_num, motor_num;
    char *axis;
    double u2c;

    pthread_mutex_lock( &(mp->mutex));

    u2c      = lsredis_getd(  mp->u2c);
    motor_num = lsredis_getl(  mp->motor_num);
    coord_num = lsredis_getl(  mp->coord_num);
    axis      = lsredis_getstr( mp->axis);

    if( u2c == 0.0) {
        //
        // Shouldn't try moving a motor that has no units defined
        //
        pthread_mutex_unlock( &(mp->mutex));
        return;
    }
    mp->requested_position = requested_position;
    mp->not_done          = 1;
    mp->motion_seen       = 0;
    mp->requested_pos_cnts = u2c * requested_position;
    requested_pos_cnts = mp->requested_pos_cnts;

    if( use_jog || axis == NULL || *axis == 0) {
        use_jog = 1;
    } else {
        use_jog = 0;
        q100 = 1 << (coord_num -1);
    }

    pthread_mutex_unlock( &(mp->mutex));

    if( use_jog) {
        snprintf( s, sizeof(s)-1, "##d j=%d", motor_num, requested_pos_cnts);
    } else {

        //
        // Make sure the coordinate system is not moving something, wait if it is
        // TODO: put in a timeout so we have a way out if something goes wrong
        // TODO: are we sure this thread is not the one moving it?
        //
        pthread_mutex_lock( &lspmac_moving_mutex);
        lslogging_log_message( "lspmac_moveabs_queue: waiting
            for previous moves to end.  lspmac_moving_flags = %0x", lspmac_moving_flags
        );
        while( (lspmac_moving_flags & q100) != 0)
            pthread_cond_wait( &lspmac_moving_cond, &
                lspmac_moving_mutex);
        pthread_mutex_unlock( &lspmac_moving_mutex);
        lslogging_log_message( "lspmac_moveabs_queue: Done.
            lspmac_moving_flags = %0x", lspmac_moving_flags);

        //
        // Set the "we are moving this coordinate system" flag
        //
        lspmac_SockSendline( "M5075=(M5075 | %d)", q100);

        switch( *axis) {
        case 'A':
            snprintf( s, sizeof(s)-1, "##d Q16=%d Q100=%d B146R", coord_num,
                requested_pos_cnts, q100);
            break;

```

```

case 'B':
    snprintf( s, sizeof(s)-1, "%d Q17=%d Q100=%d B147R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'C':
    snprintf( s, sizeof(s)-1, "%d Q18=%d Q100=%d B148R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'X':
    snprintf( s, sizeof(s)-1, "%d Q10=%d Q100=%d B140R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'Y':
    snprintf( s, sizeof(s)-1, "%d Q11=%d Q100=%d B141R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'Z':
    snprintf( s, sizeof(s)-1, "%d Q12=%d Q100=%d B142R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'U':
    snprintf( s, sizeof(s)-1, "%d Q13=%d Q100=%d B143R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'V':
    snprintf( s, sizeof(s)-1, "%d Q14=%d Q100=%d B144R", coord_num,
        requested_pos_cnts, q100);
    break;

case 'W':
    snprintf( s, sizeof(s)-1, "%d Q15=%d Q100=%d B145R", coord_num,
        requested_pos_cnts, q100);
    break;
}

//
// Make sure the flag has been seen
//
pthread_mutex_lock( &lspmac_moving_mutex);
lslogging_log_message( "lspmac_moveabs_queue: waiting
    for moving flag to propagate. lspmac_moving_flags = %0x", lspmac_moving_flags
);
while( (lspmac_moving_flags & q100) == 0)
    pthread_cond_wait( &lspmac_moving_cond, &
        lspmac_moving_mutex);
pthread_mutex_unlock( &lspmac_moving_mutex);
lslogging_log_message( "lspmac_moveabs_queue: Done.
    lspmac_moving_flags = %0x", lspmac_moving_flags);
}
pthread_mutex_lock( &(mp->mutex));
mp->pq = lspmac_SockSendline_nr( s);
pthread_mutex_unlock( &(mp->mutex));

free( axis);
}

```

5.5.4.33 void lspmac_move_or_jog_preset_queue(lspmac_motor_t * mp, char * preset, int use_jog)

move using a preset value

Parameters

in	<i>mp</i>	Our motor
in	<i>preset</i>	the name of the preset
	<i>use_jog</i>	[in] 1 to force jog, 0 to try motion prog

Definition at line 2261 of file lspmac.c.

```

{
double pos;
int err;

```

```

if( preset == NULL || *preset == 0)
    return;

err = lsredis_find_preset( mp->name, preset, &pos);

if( err != 0)
    lspmac_move_or_jog_abs_queue( mp, pos, use_jog)
    ;
}

```

5.5.4.34 void lspmac_move_preset_queue (lspmac_motor_t * mp, char * preset_name)

Move a given motor to one of its preset positions.

No movement if the preset is not found.

Parameters

<i>mp</i>	lspmac motor pointer
<i>name</i>	Name of the preset to use

Definition at line 1928 of file lspmac.c.

```

{
double pos;
int err;

lslogging_log_message( "lspmac_move_preset_queue: Called
    with motor %s and preset named '%s'", mp->name, preset_name);

err = lsredis_find_preset( mp->name, preset_name, &pos
    );
if( err == 0)
    return;

mp->moveAbs( mp, pos);
lslogging_log_message( "lspmac_move_preset_queue: moving
    %s to preset '%s' (%f)", mp->name, preset_name, pos);
}

```

5.5.4.35 void lspmac_moveabs_blight_factor_queue (lspmac_motor_t * mp, double pos)

Definition at line 2092 of file lspmac.c.

```

{
char *fmt;

if( pos >= 60 && pos <= 140) {
    pthread_mutex_lock( &(mp->mutex));
    *mp->actual_pos_cnts_p = pos;
    mp->position = pos;
    pthread_mutex_unlock( &(mp->mutex));

    pthread_mutex_lock( &(blight->mutex));
    fmt = lsredis_getstr( blight->redis_fmt);
    lsredis_setstr( blight->u2c, fmt, pos / 100.0);
    free( fmt);
    pthread_mutex_unlock( &(blight->mutex));

    blight->moveAbs( blight, lspmac_getPosition
        ( zoom));
}
}

```

5.5.4.36 void lspmac_moveabs_bo_queue (lspmac_motor_t * mp, double requested_position)

Move method for binary i/o motor objects.

Parameters

in	<i>mp</i>	A binary i/o motor object
in	<i>requested_ - position</i>	a 1 or a 0 request to move

Definition at line 1976 of file lspmac.c.

```

{

pthread_mutex_lock( &(mp->mutex));
mp->requested_position = requested_position == 0.0 ? 0.0 :
    1.0;
mp->requested_pos_cnts = requested_position == 0.0 ? 0 : 1;

mp->not_done = 1;
mp->motion_seen = 0;
mp->pq = lspmac_SockSendline_nr( mp->write_fmt
    , mp->requested_pos_cnts);

pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.37 void lspmac_moveabs.flight_factor_queue (lspmac_motor_t * mp, double pos)

Definition at line 2071 of file lspmac.c.

```

{

char *fmt;

if( pos >= 60 && pos <= 140) {
    pthread_mutex_lock( &(mp->mutex));
    *mp->actual_pos_cnts_p = pos;
    mp->position = pos;
    pthread_mutex_unlock( &(mp->mutex));

    pthread_mutex_lock( &(flight->mutex));

    fmt = lsredis_getstr( flight->redis_fmt);
    lsredis_setstr( flight->u2c, fmt, pos / 100.0);
    free( fmt);

    pthread_mutex_unlock( &(flight->mutex));

    flight->moveAbs( flight, lspmac_getPosition
        ( zoom));
}
}

```

5.5.4.38 void lspmac_moveabs.frontlight_oo.queue (lspmac_motor_t * mp, double pos)

"move" frontlight on/off

Definition at line 2059 of file lspmac.c.

```

{

pthread_mutex_lock( &(mp->mutex));
*mp->actual_pos_cnts_p = pos;
mp->position = pos;
pthread_mutex_unlock( &(mp->mutex));
if( pos == 0.0) {
    flight->moveAbs( flight, 0.0);
} else {
    flight->moveAbs( flight, lspmac_getPosition
        ( zoom));
}
}

```


5.5.4.39 void lspmac_moveabs_fshut_queue (lspmac_motor_t * mp, double requested_position)

Move method for the fast shutter.

Slightly more complicated than a binary io as some flags need to be set up.

Parameters

<i>mp</i>	The fast shutter motor instance
<i>requested_position</i>	1 (open) or 0 (close), really

Definition at line 1949 of file lspmac.c.

```

{
pthread_mutex_lock( &(mp->mutex));

mp->requested_position = requested_position;
mp->not_done = 1;
mp->motion_seen = 0;
mp->requested_pos_cnts = requested_position;
if( requested_position != 0 ) {
    //
    // ScanEnable=0, ManualEnable=1, ManualOn=1
    //
    mp->pq = lspmac_SockSendline_nr( "M1124=0 M1125=1
    M1126=1");
} else {
    //
    // ManualOn=0, ManualEnable=0, ScanEnable=1
    //
    mp->pq = lspmac_SockSendline_nr( "M1126=0 M1125=0
    M1124=1");
}

pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.40 void lspmac_moveabs_queue (lspmac_motor_t * mp, double requested_position)

Use coordinate system motion program, if available, to move motor to requested position.

Parameters

in	<i>mp</i>	The motor to move
in	<i>requested_position</i>	Where to move it

Definition at line 2281 of file lspmac.c.

```

{

lspmac_move_or_jog_abs_queue( mp,
    requested_position, 0);
}

```

5.5.4.41 void lspmac_moveabs_timed_queue (lspmac_motor_t * mp, double start, double delta, double time)

timed motor move

Parameters

<i>mp</i>	Our motor object
<i>start</i>	Beginning of motion
<i>delta</i>	Distance to move
<i>time</i>	to move it in (secs)

< Flags needed for wait routine

Definition at line 2002 of file lspmacc.c.

```

{
// 240          LS-CAT Timed X move
//          Q10   = Starting X value (cnts)
//          Q11   = Delta X value   (cnts)
//          Q12   = Time to run between the two points (mSec)
//          Q13   = Acceleration time (msecs)
//          Q100  = 1 << (coord sys no - 1)

int q10;        // Starting value (counts)
int q11;        // Delta (counts)
int q12;        // Time to run (msecs)
int q13;        // Acceleration time (msecs)
int q100;       // 1 << (coord sys no - 1)
int coord_num;  // our coordinate number
char s[512];    // PMAC command string buffer
double u2c;
double max_accel;

pthread_mutex_lock( &(mp->mutex));

u2c      = lsredis_getd( mp->u2c);
max_accel = lsredis_getd( mp->max_accel);
coord_num = lsredis_getl( mp->coord_num);

if( u2c == 0.0 || time <= 0.0 || max_accel <= 0.0) {
//
// Shouldn't try moving a motor that has bad motion parameters
//
pthread_mutex_unlock( &(mp->mutex));
return;
}

mp->not_done      = 1;
mp->motion_seen   = 0;

mp->requested_position = start + delta;
mp->requested_pos_cnts = u2c * mp->requested_position
;
q10 = mp->requested_pos_cnts;
q11 = u2c * delta;
q12 = 1000 * time;
q13 = q11 / q12 / max_accel;
q100 = 1 << (coord_num - 1);
pthread_mutex_unlock( &(mp->mutex));

snprintf( s, sizeof(s)-1, "%d Q10=%d Q11=%d Q12=%d Q13=%d Q100=%d B240R",
coord_num, q10, q11, q12, q13, q100);
pthread_mutex_lock( &(mp->mutex));
mp->pq = lspmacc_sockSendline_nr( s);
pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.42 void lspmacc_moveabs_wait (lspmacc_motor_t * mp)

Wait for motor to finish moving.

Assume motion already queued, now just wait

Parameters

in	<i>mp</i>	The motor object to wait for
----	-----------	------------------------------

Definition at line 2303 of file lspmacc.c.

```

{
struct timespec wt;
int return_code;
lspmacc_cmd_queue_t *pq;

//
// Copy the queue item for the most recent move request
//
pthread_mutex_lock( &(mp->mutex));
pq = mp->pq;

```

```

pthread_mutex_unlock( &(mp->mutex));

pthread_mutex_lock( &pmac_queue_mutex);
//
// wait for the command to be sent
//
while( pq->time_sent.tv_sec==0)
    pthread_cond_wait( &pmac_queue_cond, &pmac_queue_mutex
    );

//
// set the timeout to be long enough after we sent the motion request to
// ensure that
// we will have read back the motor moving status but not so long that the
// timeout causes
// problems;
//
wt.tv_sec = pq->time_sent.tv_sec;
wt.tv_nsec = pq->time_sent.tv_nsec + 500000000;

pthread_mutex_unlock( &pmac_queue_mutex);

if( wt.tv_nsec >= 1000000000) {
    wt.tv_nsec -= 1000000000;
    wt.tv_sec += 1;
}

//
// wait for the motion to have started
// This will time out if the motion ends before we can read the status back
// hence the added complication of time stamp of the sent packet.
//

return_code=0;

pthread_mutex_lock( &(mp->mutex));
while( mp->motion_seen == 0 && return_code == 0)
    return_code = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &
    wt);

if( return_code == 0) {
    //
    // wait for the motion that we know has started to finish
    //
    while( mp->not_done)
        pthread_cond_wait( &(mp->cond), &(mp->mutex));
}

//
// if return code was not 0 then we know we shouldn't wait for not_done flag.
// In this case the motion ended before we read the status registers
//
pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.43 void Ispmac.movedac.queue(Ispmac_motor_t * mp, double requested_position)

Move method for dac motor objects (ie, lights)

Parameters

in	<i>mp</i>	Our motor
in	<i>requested_position</i>	Desired x postion (look up and send y position)

Definition at line 1858 of file Ispmac.c.

```

{
    char s[512];
    double y;
    double u2c;

    pthread_mutex_lock( &(mp->mutex));

    u2c = lsredis_getd( mp->u2c);
    mp->requested_position = requested_position;
}

```

```

if( mp->nlut > 0 && mp->lut != NULL) {
    mp->requested_pos_cnts = u2c * lspmac_lut( mp->
        nlut, mp->lut, requested_position);
    mp->not_done = 1;
    mp->motion_seen = 0;

    //
    // By convention requested_pos_cnts scales from 0 to 100
    // for the lights u2c converts this to 0 to 16,000
    // for the scintillator focus this is 0 to 32,000
    //
    snprintf( s, sizeof(s)-1, "%s=%d", mp->dac_mvar, mp->
        requested_pos_cnts);
    mp->pq = lspmac_SockSendline_nr( s);
}

pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.44 void lspmac_movezoom_queue (lspmac_motor_t * mp, double requested_position)

Move method for the zoom motor.

Parameters

in	<i>mp</i>	the zoom motor
in	<i>requested_ - position</i>	our desired zoom

Definition at line 1893 of file lspmac.c.

```

{
    char s[512];
    double y;
    int motor_num;

    pthread_mutex_lock( &(mp->mutex));

    motor_num = lsredis_getl( mp->motor_num);

    mp->requested_position = requested_position;

    if( mp->nlut > 0 && mp->lut != NULL) {
        y = lspmac_lut( mp->nlut, mp->lut, requested_position);

        mp->requested_pos_cnts = (int)y;
        mp->not_done = 1;
        mp->motion_seen = 0;

        snprintf( s, sizeof(s)-1, "##d j=%d", motor_num, mp->requested_pos_cnts
            );
        mp->pq = lspmac_SockSendline_nr( s);
    }
    pthread_mutex_unlock( &(mp->mutex));
}

```

5.5.4.45 void lspmac_next_state ()

State machine logic.

Given the current state, generate the next one

Definition at line 1717 of file lspmac.c.

```

{

    //

```

```

// Connect to the pmac and perhaps initialize it.
// OK, this is slightly more than just the state
// machine logic...
//
if( ls_pmac_state == LS_PMAC_STATE_DETACHED
    ) {
    //
    // TODO (eventually)
    // This ip address wont change in a single PMAC installation
    // We'll need to audit the code if we decide to implement
    // multiple PMACs so might as well wait til then.
    //
    lsConnect( "192.6.94.5");

    //
    // If the connect was successful we can proceed with the initialization
    //
    if( ls_pmac_state != LS_PMAC_STATE_DETACHED
        ) {
        lspmac_SockFlush();

        //
        // Harvest the I and M variables in case we need them
        // one day.
        //
        if( getmvars ) {
            lspmac_GetAllMVars();
            getmvars = 0;
        }

        if( getivars ) {
            lspmac_GetAllIVars();
            getivars = 0;
        }
    }
}

//
// Check the command queue and perhaps go to the "Send Command" state.
//
if( ls_pmac_state == LS_PMAC_STATE_IDLE &&
    ethCmdOn != ethCmdOff )
    ls_pmac_state = LS_PMAC_STATE_SC;

//
// Set the events flag
// to tell poll what we are waiting for.
//
switch( ls_pmac_state ) {
case LS_PMAC_STATE_DETACHED:
    //
    // there shouldn't be a valid fd, so ignore the events
    //
    pmacfd.events = 0;
    break;

case LS_PMAC_STATE_IDLE:
    if( ethCmdOn == ethCmdOff ) {
        //
        // Anytime we are idle we want to
        // get the status of the PMAC
        //
        lspmac_get_status();
    }

//
// These state require that we listen for packets
//
case LS_PMAC_STATE_WACK_NFR:
case LS_PMAC_STATE_WACK:
case LS_PMAC_STATE_WACK_CC:
case LS_PMAC_STATE_WACK_RR:
case LS_PMAC_STATE_WCR:
case LS_PMAC_STATE_WGB:
case LS_PMAC_STATE_GMR:
    pmacfd.events = POLLIN;
    break;

//
// These state require that we send packets out.
//
case LS_PMAC_STATE_SC:
case LS_PMAC_STATE_CR:

```

```

case LS_PMAC_STATE_RR:
case LS_PMAC_STATE_GB:
    //
    // Sad fact: PMAC will fail to process commands if we send them too
    // quickly.
    // We deal with that by waiting a tad before we let poll tell us the PMAC
    // socket is ready to write.
    //
    gettimeofday( &now, NULL);
    if( ((now.tv_sec * 1000000. + now.tv_usec) - (pmac_time_sent.tv_sec
    * 1000000. + pmac_time_sent.tv_usec)) < PMAC_MIN_CMD_TIME) {
        pmacfd.events = 0;
    } else {
        pmacfd.events = POLLOUT;
    }
    break;
}
}

```

5.5.4.46 void lspmac_pmacmotor_read(lspmac_motor_t * mp)

Read the position and status of a normal PMAC motor.

Parameters

in	<i>mp</i>	Our motor
----	-----------	-----------

Definition at line 1247 of file lspmac.c.

```

{
char s[512], *sp;
int homing1, homing2;
double u2c;
int motor_num;
char *fmt;
pthread_mutex_lock( &(mp->mutex));

//
// if this time and last time were both "in position"
// and the position changed significantly then log the event
//
// On E omega has been observed to change by 0x10000 on its own
// with no real motion.
//
if( mp->status2 & 1 && mp->status2 == *mp->status2_p
    && abs( mp->actual_pos_cnts - *mp->actual_pos_cnts_p
    ) > 256) {
    // lslogging_log_message( "Instantaneous change: %s old status1: %0x,
    // new status1: %0x, old status2: %0x, new status2: %0x, old cnts: %0x, new cnts:
    // %0x",
    // mp->name, mp->status1, *mp->status1_p, mp->status2,
    // *mp->status2_p, mp->actual_pos_cnts, *mp->actual_pos_cnts_p);

    //
    // At this point we'll just log the event and return
    // There is no reason to believe the change is real.
    //
    // There is a non-zero probability that the first value is the bad one and
    // any value afterwards will be taken as
    // wrong. Homing (or moving) the motor should fix this. There is a
    // non-zero probability that it can happen
    // two or more times in a row after moving.
    //
    // TODO: account for the case where mp->actual_pos_cnts is the bad value.
    //
    // TODO: Is this a problem when the motor is moving? Can we detect it?
    //
    // TODO: Think of the correct change value here (currently 256) that works
    // for all motors
    // or have this value configurable
    //
    pthread_mutex_unlock( &(mp->mutex));
    return;
}

// Send an event if inPosition has changed
//
if( (mp->status2 & 0x000001) != (*mp->status2_p & 0x000001))

```

```

    {
        lsevents_send_event( "%s %s", mp->name, (*mp->
            status2_p & 0x000001) ? "In Position" : "Moving");
    }

    // Get some values we might need later
    //
    u2c      = lsredis_getd( mp->u2c);
    motor_num = lsredis_getl( mp->motor_num);

    //
    // maybe look for omega zero crossing
    //
    if( motor_num == 1 && omega_zero_search && *mp->
        actual_pos_cnts_p >= 0 && mp->actual_pos_cnts <
        0) {
        int secs, nsecs;

        if( omega_zero_velocity > 0.0) {
            secs = *mp->actual_pos_cnts_p / omega_zero_velocity
                ;
            nsecs = (*mp->actual_pos_cnts_p / omega_zero_velocity
                - secs) * 1000000000;

            omega_zero_time.tv_sec = lspmac_status_time
                .tv_sec - secs;
            omega_zero_time.tv_nsec = lspmac_status_time
                .tv_nsec;
            if( omega_zero_time.tv_nsec < nsecs) {
                omega_zero_time.tv_sec -= 1;
                omega_zero_time.tv_nsec += 1000000000;
            }
            omega_zero_time.tv_nsec -= nsecs;

            lsevents_send_event( "omega crossed zero");
            lslogging_log_message("lspmac_motor_read: omega zero
                secs %d nsecs %d ozt.tv_sec %ld ozt.tv_nsec %ld, motor cnts %d",
                secs, nsecs, omega_zero_time.tv_sec,
                omega_zero_time.tv_nsec, *mp->actual_pos_cnts_p
            );
        }
        omega_zero_search = 0;
    }

    // Make local copies so we can inspect them in other threads
    // without having to grab the status mutex
    //
    mp->status1 = *mp->status1_p;
    mp->status2 = *mp->status2_p;
    mp->actual_pos_cnts = *mp->actual_pos_cnts_p;

    //
    // See if we are done moving, ie, in position
    //
    if( mp->status2 & 0x000001) {
        if( mp->not_done) {
            mp->not_done = 0;
            pthread_cond_signal( &(mp->cond));
        }
        else if( mp->not_done == 0) {
            mp->not_done = 1;
        }
    }

    // See if the motor is moving
    //
    //          move timer          homing
    //          123456              123456
    if( mp->status1 & 0x020000 || mp->status1 & 0x000400) {
        if( mp->motion_seen == 0) {
            mp->motion_seen = 1;
            pthread_cond_signal( &(mp->cond));
        }
    }

    mvwprintw( mp->win, 2, 1, "%s", LS_DISPLAY_WINDOW_WIDTH
        -2, " ");
    mvwprintw( mp->win, 2, 1, "%d cts", LS_DISPLAY_WINDOW_WIDTH
        -6, mp->actual_pos_cnts);
    mvwprintw( mp->win, 3, 1, "%s", LS_DISPLAY_WINDOW_WIDTH
        -2, " ");

    if( mp->nlut > 0 && mp->lut != NULL) {
        mp->position = lspmac_rlut( mp->nlut, mp->lut, mp
            ->actual_pos_cnts);
    } else {

```

```

    if( u2c != 0.0) {
        mp->position = mp->actual_pos_cnts / u2c;
    } else {
        mp->position = mp->actual_pos_cnts;
    }
}

fmt = lsredis_getstr( mp->printf_fmt);
snprintf( s, sizeof(s)-1, fmt, 8, mp->position);
free( fmt);

// set flag if we are not homed
homing1 = 0;
// ~ (homed flag)
if( mp->homing == 0 && (~mp->status2 & 0x000400) != 0) {
    homing1 = 1;
}

// set flag if we are homing and in open loop
homing2 = 0;
// open loop
if( mp->homing == 1 && (mp->status1 & 0x040000) != 0) {
    homing2 = 1;
}
// maybe reset homing flag
// homed flag in position flag
if( mp->homing == 2 && (mp->status2 & 0x000400 != 0) && (mp->
    status2 & 0x000001 != 0))
    mp->homing = 0;

s[sizeof(s)-1] = 0;
mvwprintw( mp->win, 3, 1, "%*s", LS_DISPLAY_WINDOW_WIDTH
    -6, s);

mvwprintw( mp->win, 4, 1, "%*x", LS_DISPLAY_WINDOW_WIDTH
    -2, mp->status1);
mvwprintw( mp->win, 5, 1, "%*x", LS_DISPLAY_WINDOW_WIDTH
    -2, mp->status2);
sp = "";
if( mp->status2 & 0x000002)
    sp = "Following Warning";
else if( mp->status2 & 0x000004)
    sp = "Following Error";
else if( mp->status2 & 0x000020)
    sp = "I2T Amp Fault";
else if( mp->status2 & 0x000008)
    sp = "Amp. Fault";
else if( mp->status2 & 0x000800)
    sp = "Stopped on Limit";
else if( mp->status1 & 0x040000)
    sp = "Open Loop";
else if( ~(mp->status1) & 0x080000)
    sp = "Motor Disabled";
else if( mp->status1 & 0x000400)
    sp = "Homing";
else if( (mp->status1 & 0x600000) == 0x600000)
    sp = "Both Limits Tripped";
else if( mp->status1 & 0x200000)
    sp = "Positive Limit";
else if( mp->status1 & 0x400000)
    sp = "Negative Limit";
else if( ~(mp->status2) & 0x000400)
    sp = "Not Homed";
else if( mp->status2 & 0x000001)
    sp = "In Position";

mvwprintw( mp->win, 6, 1, "%*s", LS_DISPLAY_WINDOW_WIDTH
    -2, sp);
wnoutrefresh( mp->win);

strncpy( mp->statuss, sp, sizeof( mp->statuss)-1);
mp->statuss[sizeof(mp->statuss)-1] = 0;

pthread_mutex_unlock( &(mp->mutex));

if( homing1)
    lspmac_homed1_queue( mp);

if( homing2)
    lspmac_homed2_queue( mp);

lspmac_status_last_time.tv_sec = lspmac_status_time
    .tv_sec;
lspmac_status_last_time.tv_nsec = lspmac_status_time
    .tv_nsec;
}

```


5.5.4.47 `pmac_cmd_queue_t* lspmac_pop_queue ()`

Remove the oldest queue item.

Used to send command to PMAC. Note that there is a separate reply index to ensure we've know to what command a reply is referring. Returns the item.

Definition at line 556 of file lspmac.c.

```

{
    pmac_cmd_queue_t *rtn;

    pthread_mutex_lock( &pmac_queue_mutex);

    if( ethCmdOn == ethCmdOff)
        rtn = NULL;
    else {
        rtn = &(ethCmdQueue[(ethCmdOff++) %
            PMAC_CMD_QUEUE_LENGTH]);
        clock_gettime( CLOCK_REALTIME, &(rtn->time_sent));
    }
    pthread_mutex_unlock( &pmac_queue_mutex);
    return rtn;
}

```

5.5.4.48 `pmac_cmd_queue_t* lspmac_pop_reply ()`

Remove the next command queue item that is waiting for a reply.

We always need a reply to know we are done with a given command. Returns the item.

Definition at line 576 of file lspmac.c.

```

{
    pmac_cmd_queue_t *rtn;

    pthread_mutex_lock( &pmac_queue_mutex);

    if( ethCmdOn == ethCmdReply)
        rtn = NULL;
    else
        rtn = &(ethCmdQueue[(ethCmdReply++) %
            PMAC_CMD_QUEUE_LENGTH]);

    pthread_mutex_unlock( &pmac_queue_mutex);
    return rtn;
}

```

5.5.4.49 `pmac_cmd_queue_t* lspmac_push_queue (pmac_cmd_queue_t * cmd)`

Put a new command on the queue.

Pointer is returned so caller can evaluate the time command was actually sent.

Parameters

<i>cmd</i>	Command to send to the PMAC
------------	-----------------------------

Definition at line 532 of file lspmac.c.

```

{
    pmac_cmd_queue_t *rtn;

    pthread_mutex_lock( &pmac_queue_mutex);
    rtn = &(ethCmdQueue[(ethCmdOn++) % PMAC_CMD_QUEUE_LENGTH
    ]);
    memcpy( rtn, cmd, sizeof( pmac_cmd_queue_t));
    rtn->time_sent.tv_sec = 0;
    rtn->time_sent.tv_nsec = 0;
    pthread_cond_signal( &pmac_queue_cond);
}

```

```
pthread_mutex_unlock( &pmac_queue_mutex);

return rtn;
}
```

5.5.4.50 void lspmac_Reset ()

Clear the queue and put the PMAC into a known state.

Definition at line 653 of file lspmac.c.

```
{
ls_pmac_state = LS_PMAC_STATE_IDLE;

// clear queue
ethCmdReply = ethCmdOn;
ethCmdOff   = ethCmdOn;

lspmac_SockFlush();
}
```

5.5.4.51 double lspmac_rlut (int nlut, double * lut, double y)

Parameters

in	<i>nlut</i>	number of entries in lookup table
in	<i>lut</i>	our lookup table
in	<i>y</i>	the y value for which we need an x

Definition at line 368 of file lspmac.c.

```
{
int i, foundone, up;
double m;
double y1, y2, x1, x2, x;

foundone = 0;
if( lut != NULL && nlut > 1) {

    if( lut[1] < lut[2*nlut-1])
        up = 1;
    else
        up = 0;

    for( i=0; i < 2*nlut; i += 2) {
        x1 = lut[i];
        y1 = lut[i+1];
        if( i < 2*nlut - 2) {
            x2 = lut[i+2];
            y2 = lut[i+3];
        }
        if( i==0 && ( up ? y1 > y : y1 < y)) {
            x = x1;
            foundone = 1;
            break;
        }
        if( y1 == y) {
            x = x1;
            foundone = 1;
            break;
        }
        if( (i < 2*nlut-2) && (up ? y < y2 : y > y2)) {
            m = (x2 - x1) / (y2 - y1);
            x = m * (y - y1) + x1;
            foundone = 1;
            break;
        }
    }
    if( foundone == 0 ) {
        x = lut[2*(nlut-1)];
    }
    return x;
}
return 0.0;
}
```

5.5.4.52 void lspmac_run ()

find a postion for a given preset name

Parameters

<i>mp</i>	Motor pointer
<i>name</i>	The preset to search for
<i>err</i>	set to non-zero on error, ignored if nullStart up the lspmac thread

Definition at line 2714 of file lspmac.c.

```

    {
char **inits;
lspmac_motor_t *mp;
int i;
int active;

pthread_create( &pmac_thread, NULL, lspmac_worker,
    NULL);

lsevents_add_listener( "CryoSwitchChanged",
    lspmac_cryoSwitchChanged_cb);
lsevents_add_listener( "scint In Position",
    lspmac_scint_inPosition_cb);
lsevents_add_listener( "scintDried",
    lspmac_scint_dried_cb);
lsevents_add_listener( "backLight 1",
    lspmac_backLight_up_cb);
lsevents_add_listener( "backLight 0",
    lspmac_backLight_down_cb);
lsevents_add_listener( "cam.zoom In Position",
    lspmac_light_zoom_cb);

//
// Initialize the MD2 pmac (ie, turn on the right plcc's etc)
//
for( inits = lsredis_get_string_array(lspmac_md2_init
); *inits != NULL; inits++) {
    lspmac_SockSendline( *inits);
    // lslogging_log_message( "lspmac_init: pmac init '%s'", *inits);
}

//
// Initialize the pmac's support for each motor
// (ie, set the various flag for when a motor is active or not)
//
for( i=0; i<lspmac_nmotors; i++) {
    mp = &(lspmac_motors[i]);
    active = lsredis_getb( mp->active);

    // if there is a problem with "active" then don't do anything
    // On the other hand, various combinations of yes/no true/fals 1/0 should
    work
    //
    switch( active) {
case 1:
    inits = lsredis_get_string_array( mp->active_init
);
    break;

case 0:
    inits = lsredis_get_string_array( mp->active_init
);
    break;

default:
    inits = NULL;
}

if( inits != NULL) {
    while( *inits != NULL) {
        lspmac_SockSendline( *inits);
        // lslogging_log_message( "lspmac_init: %s init '%s'", mp->name,
        *inits);
        inits++;
    }
}
}
}

```

5.5.4.53 void lspmac_scint_dried_cb (char * event)

Turn off the dryer.

Parameters

<i>event</i>	required by protocol
--------------	----------------------

Definition at line 2698 of file lspmac.c.

```

{
    lslogging_log_message( "lspmac_scint_dried_cb: Stopping
        dryer");
    dryer->moveAbs( dryer, 0.0);
}

```

5.5.4.54 void lspmac_scint_inPosition_cb (char * event)

Maybe start drying off the scintillator.

Parameters

<i>event</i>	required by protocol
--------------	----------------------

Definition at line 2637 of file lspmac.c.

```

{
    double pos;
    double cover;
    int err;

    pthread_mutex_lock( &(amp;scint->mutex));
    pos = scint->position;
    err = lsredis_find_preset( scint->name, "Cover",
        &pos);
    pthread_mutex_unlock( &(scint->mutex));

    lslogging_log_message( "lspmac_scint_inPosition_cb: pos
        %f, cover %f, diff %f, err %d", pos, cover, fabs( pos-cover), err);

    if( err == 0)
        return;

    if( fabs( pos - cover) <= 0.1) {
        dryer->moveAbs( dryer, 1.0);
        lslogging_log_message( "lspmac_scint_inPosition_cb:
            Starting dryer");
        lstimer_add_timer( "scintDried", 1, 120, 0);
    }
}

```

5.5.4.55 pmac_cmd_queue_t* lspmac_send_command (int rqType, int rq, int wValue, int wIndex, int wLength, unsigned char * data, void(*) (pmac_cmd_queue_t *, int, unsigned char *) responseCB, int no_reply)

Compose a packet and send it to the PMAC.

This is the meat of the PMAC communications routines. The queued command is returned.

Parameters

in	<i>rqType</i>	VR_UPLOAD or VR_DOWNLOAD
in	<i>rq</i>	PMAC command (see PMAC User Manual)
in	<i>wValue</i>	Command argument 1
in	<i>wIndex</i>	Command argument 2
in	<i>wLength</i>	Length of data array
in	<i>data</i>	Data array (or NULL)

in	<i>responseCB</i>	Function to call when a response is read from the PMAC
in	<i>no_reply</i>	Flag, non-zero means no reply is expected

Definition at line 594 of file lspmac.c.

```

static pmac_cmd_queue_t cmd;

cmd.pcmd.RequestType = rqType;
cmd.pcmd.Request      = rq;
cmd.pcmd.wValue       = htons(wValue);
cmd.pcmd.wIndex       = htons(wIndex);
cmd.pcmd.wLength      = htons(wLength);
cmd.onResponse        = responseCB;
cmd.no_reply          = no_reply;

//
// Setting the message buff bData requires a bit more care to avoid over
// filling it
// or sending garbage in the unused bytes.
//

if( wLength > sizeof( cmd.pcmd.bData)) {
    //
    // Bad things happen if we do not catch this case.
    //
    lslogging_log_message( "Message Length %d longer than
        maximum of %ld, aborting", wLength, sizeof( cmd.pcmd.bData));
    exit( -1);
}
if( data == NULL) {
    memset( cmd.pcmd.bData, 0, sizeof( cmd.pcmd.bData));
} else {
    //
    // This could leave bData non-null terminated. I do not know if this is a
    // problem.
    //
    if( wLength > 0)
        memcpy( cmd.pcmd.bData, data, wLength);
    if( wLength < sizeof( cmd.pcmd.bData))
        memset( cmd.pcmd.bData + wLength, 0, sizeof( cmd.pcmd.bData
            ) - wLength);
}

return lspmac_push_queue( &cmd);
}

```

5.5.4.56 void lspmac_sendcmd (void(*) (pmac_cmd_queue_t *, int, unsigned char *) responseCB, char * fmt, ...)

PMAC command with call back.

Parameters

in	<i>responseCB</i>	our callback routine
in	<i>fmt</i>	printf style format string

Definition at line 1697 of file lspmac.c.

```

static char tmps[1024];
va_list arg_ptr;

va_start( arg_ptr, fmt);
vsnprintf( tmps, sizeof(tmps)-1, fmt, arg_ptr);
tmps[sizeof(tmps)-1]=0;
va_end( arg_ptr);

lspmac_send_command( VR_DOWNLOAD,
    VR_PMAC_SENDBLINE, 0, 0, strlen(tmps), tmps, responseCB, 0);
}

```

5.5.4.57 void lspmac_sendcmd_nocb (char * *fmt*, ...)

Send a command that does not need to deal with the reply.

Parameters

in	<i>fmt</i>	A printf style format string
----	------------	------------------------------

Definition at line 1678 of file lspmac.c.

```

static char tmps[1024];
va_list arg_ptr;

va_start( arg_ptr, fmt);
vsnprintf( tmps, sizeof(tmps)-1, fmt, arg_ptr);
tmps[sizeof(tmps)-1]=0;
va_end( arg_ptr);

lspmac_send_command( VR_DOWNLOAD,
                    VR_PMAC_SENDFLINE, 0, 0, strlen(tmps), tmps, NULL, 0);
}

```

5.5.4.58 void lspmac_SendControlReplyPrintCB (pmac_cmd_queue_t * *cmd*, int *nreceived*, unsigned char * *buff*)

Receive a reply to a control character Print a "printable" version of the character to the terminal Followed by a hex dump of the response.

Parameters

in	<i>cmd</i>	Queue item this is a reply to
in	<i>nreceived</i>	Number of bytes received
in	<i>buff</i>	Buffer of bytes received

Definition at line 915 of file lspmac.c.

```

{
pthread_mutex_lock( &ncurses_mutex);
wprintw( term_output, "control-%c: ", '@'+ ntohs(cmd->pcmd.
wValue));
pthread_mutex_unlock( &ncurses_mutex);
hex_dump( nreceived, buff);
pthread_mutex_lock( &ncurses_mutex);
wnoutrefresh( term_output);
wnoutrefresh( term_input);
douupdate();
pthread_mutex_unlock( &ncurses_mutex);
}

```

5.5.4.59 void lspmac_Service (struct pollfd * *evt*)

Service routine for packet coming from the PMAC.

All communications is asynchronous so this is the only place incoming packets are handled

Parameters

in	<i>evt</i>	pollfd object returned by poll
----	------------	--------------------------------

Definition at line 700 of file lspmac.c.

```

{
static unsigned char *receiveBuffer = NULL; // the buffer inwhich to stick
our incoming characters
static int receiveBufferSize = 0; // size of receiveBuffer

```

```

static int receiveBufferIn = 0;           // next location to write to in
    receiveBuffer
pmac_cmd_queue_t *cmd;                   // maybe the
    command we are servicing
ssize_t nsent, nread;                     // nbytes dealt with
int i;                                    // loop counter
int foundEOCR;                            // end of command response flag

if( evt->revents & (POLLERR | POLLHUP | POLLNVAL)) {
    if( evt->fd != -1) {
        close( evt->fd);
        evt->fd = -1;
    }
    ls_pmac_state = LS_PMAC_STATE_DETACHED;
    return;
}

if( evt->revents & POLLOUT) {

    switch( ls_pmac_state) {
    case LS_PMAC_STATE_DETACHED:
        break;
    case LS_PMAC_STATE_IDLE:
        break;

    case LS_PMAC_STATE_SC:
        cmd = lspmac_pop_queue();
        if( cmd != NULL) {
            if( cmd->pcmd.Request == VR_PMAC_GETMEM) {
                nsent = send( evt->fd, cmd, pmac_cmd_size, 0);
                if( nsent != pmac_cmd_size) {
                    lslogging_log_message( "Could only send %d of
%d bytes....Not good.", (int)nsent, (int)(pmac_cmd_size));
                }
            } else {
                nsent = send( evt->fd, cmd, pmac_cmd_size + ntohs(cmd->
pcmd.wLength), 0);
                gettimeofday( &pmac_time_sent, NULL);
                if( nsent != pmac_cmd_size + ntohs(cmd->pcmd.wLength
)) {
                    lslogging_log_message( "Could only send %d of
%d bytes....Not good.", (int)nsent, (int)(pmac_cmd_size + ntohs(cmd
->pcmd.wLength)));
                }
            }
        }
        if( cmd->pcmd.Request == VR_PMAC_SENDCTRLCHAR
)
            ls_pmac_state = LS_PMAC_STATE_WACK_CC
;
        else if( cmd->pcmd.Request == VR_PMAC_GETMEM)
            ls_pmac_state = LS_PMAC_STATE_GMR;
        else if( cmd->no_reply == 0)
            ls_pmac_state = LS_PMAC_STATE_WACK;
        else
            ls_pmac_state = LS_PMAC_STATE_WACK_NFR
;
        break;

    case LS_PMAC_STATE_CR:
        nsent = send( evt->fd, &cr_cmd, pmac_cmd_size, 0);
        gettimeofday( &pmac_time_sent, NULL);
        ls_pmac_state = LS_PMAC_STATE_WCR;
        break;

    case LS_PMAC_STATE_RR:
        nsent = send( evt->fd, &rr_cmd, pmac_cmd_size, 0);
        gettimeofday( &pmac_time_sent, NULL);
        ls_pmac_state = LS_PMAC_STATE_WACK_RR;
        break;

    case LS_PMAC_STATE_GB:
        nsent = send( evt->fd, &gb_cmd, pmac_cmd_size, 0);
        gettimeofday( &pmac_time_sent, NULL);
        ls_pmac_state = LS_PMAC_STATE_WGB;
        break;
    }
}

if( evt->revents & POLLIN) {

    if( receiveBufferSize - receiveBufferIn < 1400) {
        unsigned char *newbuff;

        receiveBufferSize += 1400;
        newbuff = calloc( receiveBufferSize, sizeof( unsigned char));

```

```

    if( newbuff == NULL) {
        lslogging_log_message( "Out of memory");
        exit( -1);
    }
    if( receiveBuffer != NULL) {
        memcpy( newbuff, receiveBuffer, receiveBufferIn);
        free(receiveBuffer);
    }
    receiveBuffer = newbuff;
}

nread = read( evt->fd, receiveBuffer + receiveBufferIn, 1400);

foundEOCR = 0;
if( ls_pmac_state == LS_PMAC_STATE_GMR) {
    //
    // get memory returns binary stuff, don't try to parse it
    //
    receiveBufferIn += nread;
} else {
    //
    // other commands end in 6 if OK, 7 if not
    //
    for( i=receiveBufferIn; i<receiveBufferIn+nread; i++) {
        if( receiveBuffer[i] == 7) {
            //
            // Error condition
            //
            lspmac_Error( &(receiveBuffer[i]));
            receiveBufferIn = 0;
            return;
        }
        if( receiveBuffer[i] == 6) {
            //
            // End of command response
            //
            foundEOCR = 1;
            receiveBuffer[i] = 0;
            break;
        }
    }
    receiveBufferIn = i;
}

cmd = NULL;

switch( ls_pmac_state) {
case LS_PMAC_STATE_WACK_NFR:
    receiveBuffer[--receiveBufferIn] = 0;
    cmd = lspmac_pop_reply();
    ls_pmac_state = LS_PMAC_STATE_IDLE;
    break;
case LS_PMAC_STATE_WACK:
    receiveBuffer[--receiveBufferIn] = 0;
    ls_pmac_state = LS_PMAC_STATE_RR;
    break;
case LS_PMAC_STATE_WACK_CC:
    receiveBuffer[--receiveBufferIn] = 0;
    ls_pmac_state = LS_PMAC_STATE_CR;
    break;
case LS_PMAC_STATE_WACK_RR:
    receiveBufferIn -= 2;
    if( receiveBuffer[receiveBufferIn])
        ls_pmac_state = LS_PMAC_STATE_GB;
    else
        ls_pmac_state = LS_PMAC_STATE_RR;
    receiveBuffer[receiveBufferIn] = 0;
    break;
case LS_PMAC_STATE_GMR:
    cmd = lspmac_pop_reply();
    ls_pmac_state = LS_PMAC_STATE_IDLE;
    break;
case LS_PMAC_STATE_WCR:
    cmd = lspmac_pop_reply();
    ls_pmac_state = LS_PMAC_STATE_IDLE;
    break;
case LS_PMAC_STATE_WGB:
    if( foundEOCR) {
        cmd = lspmac_pop_reply();
        ls_pmac_state = LS_PMAC_STATE_IDLE;
    } else {
        ls_pmac_state = LS_PMAC_STATE_RR;
    }
    break;
}

```



```

    if( cmd != NULL && cmd->onResponse != NULL) {
        cmd->onResponse( cmd, receiveBufferIn, receiveBuffer);
        receiveBufferIn = 0;
    }
}
}

```

5.5.4.60 void lspmac_shutter_read (lspmac_motor_t * mp)

Fast shutter read routine The shutter is mildly complicated in that we need to take into account the fact that the shutter can open and close again between status updates.

This means that we need to rely on a PCL program running in the PMAC to monitor the shutter state and let us know that this has happened.

Parameters

in	mp	The motor object associated with the fast shutter
----	----	---

Definition at line 1074 of file lspmac.c.

```

{
    //
    // track the shutter state and signal if it has changed
    //
    pthread_mutex_lock( &lspmac_shutter_mutex);
    if( md2_status.fs_has_opened && !
        lspmac_shutter_has_opened && !md2_status.
        fs_is_open) {
        //
        // Here the shutter opened and closed again before we got the memo
        // Treat it as a shutter closed event
        //
        pthread_cond_signal( &lspmac_shutter_cond);
    }
    lspmac_shutter_has_opened = md2_status.
        fs_has_opened;

    if( lspmac_shutter_state != md2_status.
        fs_is_open) {
        lspmac_shutter_state = md2_status.fs_is_open
        ;
        pthread_cond_signal( &lspmac_shutter_cond);
    }

    if( md2_status.fs_is_open) {
        mvwprintw( term_status2, 1, 1, "Shutter Open  ");
        mp->position = 1;
    } else {
        mvwprintw( term_status2, 1, 1, "Shutter Closed");
        mp->position = 0;
    }

    // Not sure what kind of status makes sense to report
    mp->statuss[0] = 0;

    pthread_mutex_unlock( &lspmac_shutter_mutex);
}

```

5.5.4.61 void lspmac_SockFlush ()

Reset the PMAC socket from the PMAC side.

Puts the PMAC into a known communications state

Definition at line 646 of file lspmac.c.

```

{
    lspmac_send_command( VR_DOWNLOAD, VR_PMAC_FLUSH
        , 0, 0, 0, NULL, NULL, 1);
}

```

5.5.4.62 `pmac_cmd_queue_t*` `lspmac_SockGetmem (int offset, int nbytes)`

Request a chunk of memory to be returned.

Not currently used

Parameters

in	<i>offset</i>	Offset in PMAC Double Buffer
in	<i>nbytes</i>	Number of bytes to request

Definition at line 952 of file `lspmac.c`.

```

{
return lspmac_send_command( VR_UPLOAD,
    VR_PMAC_GETMEM, offset, 0, nbytes, NULL, lspmac_GetmemReplyCB
    , 0);
}

```

5.5.4.63 `pmac_cmd_queue_t*` `lspmac_SockSendControlCharPrint (char c)`

Send a control character.

Parameters

<i>c</i>	The control character to send
----------	-------------------------------

Definition at line 1000 of file `lspmac.c`.

```

{
return lspmac_send_command( VR_DOWNLOAD,
    VR_PMAC_SENDCTRLCHAR, c, 0, 0, NULL,
    lspmac_SendControlReplyPrintCB, 0);
}

```

5.5.4.64 `pmac_cmd_queue_t*` `lspmac_SockSendline (char * fmt, ...)`

Send a one line command.

Uses printf style arguments.

Parameters

in	<i>fmt</i>	Printf style format string
----	------------	----------------------------

Definition at line 962 of file `lspmac.c`.

```

{
va_list arg_ptr;
char payload[1400];

va_start( arg_ptr, fmt);
vsnprintf( payload, sizeof(payload)-1, fmt, arg_ptr);
payload[ sizeof(payload)-1] = 0;
va_end( arg_ptr);

lslogging_log_message( payload);

return lspmac_send_command( VR_DOWNLOAD,
    VR_PMAC_SENDLINE, 0, 0, strlen( payload), payload,
    lspmac_GetShortReplyCB, 0);
}

```

5.5.4.65 `lspmac_cmd_queue_t*` `lspmac_sock_sendline_nr (char * fmt, ...)`

Send a command and ignore the response.

Parameters

<code>in</code>	<code><i>fmt</i></code>	Printf style format string
-----------------	-------------------------	----------------------------

Definition at line 981 of file `lspmac.c`.

```

{
    va_list arg_ptr;
    char s[512];

    va_start( arg_ptr, fmt);
    vsnprintf( s, sizeof(s)-1, fmt, arg_ptr);
    s[sizeof(s)-1] = 0;
    va_end( arg_ptr);

    lslogging_log_message( s);

    return lspmac_send_command( VR_DOWNLOAD,
                               VR_PMAC_SENDLINE, 0, 0, strlen( s), s, NULL, 1);
}

```

5.5.4.66 `lspmac_motor_t*` `lspmac_soft_motor_init (lspmac_motor_t * d, char * name, void (*)(lspmac_motor_t *, double) moveAbs)`

Definition at line 2501 of file `lspmac.c`.

```

{
    _lspmac_motor_init( d, name);

    d->moveAbs = moveAbs;
    d->read = lspmac_soft_motor_read;
    d->actual_pos_cnts_p = calloc( sizeof(int), 1);
    *d->actual_pos_cnts_p = 0;
}

```

5.5.4.67 `void` `lspmac_soft_motor_read (lspmac_motor_t * p)`

Dummy routine to read a soft motor.

Definition at line 2496 of file `lspmac.c`.

```

{
}

```

5.5.4.68 `void` `lspmac_video_rotate (double secs)`

Special motion program to collect centering video.

Definition at line 2114 of file `lspmac.c`.

```

{
    double q10;           // starting position (counts)
    double q11;           // delta counts
    double q12;           // milliseconds to run over delta

    double u2c;

    if( secs <= 0.0)
        return;
}

```

```

    omega_zero_search = 1;

    pthread_mutex_lock( &(omega->mutex));
    u2c = lsredis_getd( omega->u2c);

    q10 = 0;
    q11 = 360.0 * u2c;
    q12 = 1000 * secs;

    omega_zero_velocity = 360.0 * u2c / secs; //
        counts/second to back calculate zero crossing time

    omega->pq = lspmac_SockSendline_nr( "&1 Q10=%.1f
        Q11=%.1f Q12=%.1f Q13=(I117) Q14=(I116) B240R", q10, q11, q12);
    pthread_mutex_unlock( &(omega->mutex));
}

```

5.5.4.69 void* lspmac_worker (void * dummy)

Our lspmac worker thread.

Parameters

in	<i>dummy</i>	Unused but required by pthread library
----	--------------	--

Definition at line 1824 of file lspmac.c.

```

{
    while( 1) {
        int pollrtn;

        lspmac_next_state();

        if( pmacfd.fd == -1) {
            sleep( 10); // The pmac is not connected. Should we warn someone?
            //
            // This just puts us into a holding pattern until the pmac becomes
            // connected again
            //
            // TODO:
            // Check PMAC initialization logic and our queues to ensure that it is
            // sane to
            // re-initialize things. Probably bad things will happen.
            //
            continue;
        }

        pollrtn = poll( &pmacfd, 1, 10);
        if( pollrtn) {
            lspmac_Service( &pmacfd);
        }
    }
}

```

5.5.5 Variable Documentation

5.5.5.1 lspmac_motor_t* alignx

Alignment stage X.

Definition at line 83 of file lspmac.c.

5.5.5.2 lspmac_motor_t* aligny

Alignment stage Y.

Definition at line 84 of file lspmac.c.

5.5.5.3 Ispmac_motor_t* alignz

Alignment stage X.

Definition at line 85 of file Ispmac.c.

5.5.5.4 Ispmac_motor_t* anal

Polaroid analyzer motor.

Definition at line 86 of file Ispmac.c.

5.5.5.5 Ispmac_motor_t* apery

Aperture Y.

Definition at line 88 of file Ispmac.c.

5.5.5.6 Ispmac_motor_t* aperz

Aperture Z.

Definition at line 89 of file Ispmac.c.

5.5.5.7 Ispmac_motor_t* blight

Back Light DAC.

Definition at line 100 of file Ispmac.c.

5.5.5.8 Ispmac_motor_t* blight_f

Back light scale factor.

Definition at line 105 of file Ispmac.c.

5.5.5.9 Ispmac_motor_t* blight_ud

Back light Up/Down actuator.

Definition at line 103 of file Ispmac.c.

5.5.5.10 Ispmac_motor_t* capy

Capillary Y.

Definition at line 90 of file Ispmac.c.

5.5.5.11 Ispmac_motor_t* capz

Capillary Z.

Definition at line 91 of file Ispmac.c.

5.5.5.12 `lspmac_motor_t* cenx`

Centering Table X.

Definition at line 93 of file `lspmac.c`.

5.5.5.13 `lspmac_motor_t* ceny`

Centering Table Y.

Definition at line 94 of file `lspmac.c`.

5.5.5.14 `pmac_cmd_t cr_cmd` `[static]`

commands to send out "readready", "getbuffer", controlresponse (initialized in main)

Definition at line 159 of file `lspmac.c`.

5.5.5.15 `lspmac_motor_t* cryo`

Move the cryostream towards or away from the crystal.

Definition at line 107 of file `lspmac.c`.

5.5.5.16 `lspmac_bi_t* cryo_switch`

that little toggle switch for the cryo

Definition at line 111 of file `lspmac.c`.

5.5.5.17 `unsigned char dbmem[64 * 1024]` `[static]`

double buffered memory

Definition at line 149 of file `lspmac.c`.

5.5.5.18 `int dbmemIn = 0` `[static]`

next location

Definition at line 150 of file `lspmac.c`.

5.5.5.19 `lspmac_motor_t* dryer`

blow air on the scintillator to dry it off

Definition at line 108 of file `lspmac.c`.

5.5.5.20 `unsigned int ethCmdOff = 0` `[static]`

points to current command (or none if == `ethCmdOn`)

Definition at line 162 of file `lspmac.c`.

5.5.5.21 `unsigned int ethCmdOn = 0` `[static]`

points to next empty PMAC command queue position

Definition at line 161 of file lspmac.c.

5.5.5.22 `pmac_cmd_queue_t ethCmdQueue[PMAC_CMD_QUEUE_LENGTH]` `[static]`

PMAC command queue.

Definition at line 160 of file lspmac.c.

5.5.5.23 `unsigned int ethCmdReply = 0` `[static]`

Used like ethCmdOff only to deal with the pmac reply to a command.

Definition at line 163 of file lspmac.c.

5.5.5.24 `lspmac_motor_t* flight`

Front Light DAC.

Definition at line 99 of file lspmac.c.

5.5.5.25 `lspmac_motor_t* flight.f`

Front light scale factor.

Definition at line 106 of file lspmac.c.

5.5.5.26 `lspmac_motor_t* flight.oo`

Turn front light on/off.

Definition at line 104 of file lspmac.c.

5.5.5.27 `lspmac_motor_t* fluo`

Move the fluorescence detector in/out.

Definition at line 109 of file lspmac.c.

5.5.5.28 `lspmac_motor_t* fscint`

Scintillator Piezo DAC.

Definition at line 101 of file lspmac.c.

5.5.5.29 `lspmac_motor_t* fshut`

Fast shutter.

Definition at line 98 of file lspmac.c.

5.5.5.30 `pmac_cmd_t gb_cmd` `[static]`

Definition at line 159 of file `lspmac.c`.

5.5.5.31 `int getivars = 0` `[static]`

flag set at initialization to send i vars to db

Definition at line 74 of file `lspmac.c`.

5.5.5.32 `int getmvars = 0` `[static]`

flag set at initialization to send m vars to db

Definition at line 75 of file `lspmac.c`.

5.5.5.33 `lspmac_motor_t* kappa`

Kappa.

Definition at line 95 of file `lspmac.c`.

5.5.5.34 `int linesReceived = 0` `[static]`

current number of lines received

Definition at line 148 of file `lspmac.c`.

5.5.5.35 `int ls_pmac_state = LS_PMAC_STATE_DETACHED` `[static]`

Current state of the PMAC communications state machine.

Definition at line 51 of file `lspmac.c`.

5.5.5.36 `lspmac_bi_t lspmactbis[16]`

array of binary inputs

Definition at line 77 of file `lspmac.c`.

5.5.5.37 `lsredis_obj_t* lspmactmd2init` `[static]`

Definition at line 53 of file `lspmac.c`.

5.5.5.38 `lspmac_motor_t lspmactmotors[48]`

All our motors.

Definition at line 80 of file `lspmac.c`.

5.5.5.39 `pthread_cond_t lspmactmovingcond`

Wait for motor(s) to finish moving condition.

Definition at line 60 of file `lspmac.c`.

5.5.5.40 int lspmac_moving_flags

Flag used to implement motor moving condition.

Definition at line 61 of file lspmac.c.

5.5.5.41 pthread_mutex_t lspmac_moving_mutex

Coordinate moving motors between threads.

Definition at line 59 of file lspmac.c.

5.5.5.42 int lspmac_nbis = 0

number of active binary inputs

Definition at line 78 of file lspmac.c.

5.5.5.43 int lspmac_nmotors = 0

The number of motors we manage.

Definition at line 81 of file lspmac.c.

5.5.5.44 pthread_cond_t lspmac_shutter_cond

Allows waiting for the shutter status to change.

Definition at line 58 of file lspmac.c.

5.5.5.45 int lspmac_shutter_has_opened

Indicates that the shutter had opened, perhaps briefly even if the state did not change.

Definition at line 56 of file lspmac.c.

5.5.5.46 pthread_mutex_t lspmac_shutter_mutex

Coordinates threads reading shutter status.

Definition at line 57 of file lspmac.c.

5.5.5.47 int lspmac_shutter_state

State of the shutter, used to detect changes.

Definition at line 55 of file lspmac.c.

5.5.5.48 struct timespec lspmac_status_last_time [static]

Time the status was read.

Definition at line 67 of file lspmac.c.

5.5.5.49 struct timespec lspmac_status_time [static]

Time the status was read.

Definition at line 66 of file lspmac.c.

5.5.5.50 md2_status_t md2_status [static]

Buffer for MD2 Status.

Definition at line 297 of file lspmac.c.

5.5.5.51 pthread_mutex_t md2_status_mutex

Synchronize reading/writing status buffer.

Definition at line 298 of file lspmac.c.

5.5.5.52 struct timeval pmac_time_sent now [static]

used to ensure we do not send commands to the pmac too often. Only needed for non-DB commands.

Definition at line 155 of file lspmac.c.

5.5.5.53 lspmac_motor_t* omega

MD2 omega axis (the air bearing)

Definition at line 82 of file lspmac.c.

5.5.5.54 int omega_zero_search = 0 [static]

Indicate we'd really like to know when omega crosses zero.

Definition at line 63 of file lspmac.c.

5.5.5.55 struct timespec omega_zero_time

Time we believe that omega crossed zero.

Definition at line 65 of file lspmac.c.

5.5.5.56 double omega_zero_velocity = 0 [static]

rate (cnts/sec) that omega was traveling when it crossed zero

Definition at line 64 of file lspmac.c.

5.5.5.57 lspmac_motor_t* phi

Phi (not data collection axis)

Definition at line 96 of file lspmac.c.

5.5.5.58 `char* pmac_error_strs[]` `[static]`**Initial value:**

```
= {
    "ERR000: Unknown error",
    "ERR001: Command not allowed during program execution",
    "ERR002: Password error",
    "ERR003: Data error or unrecognized command",
    "ERR004: Illegal character",
    "ERR005: Command not allowed unless buffer is open",
    "ERR006: No room in buffer for command",
    "ERR007: Buffer already in use",
    "ERR008: MACRO auxiliary communication error",
    "ERR009: Program structure error (e.g. ENDIF without IF)",
    "ERR010: Both overtravel limits set for a motor in the C.S.",
    "ERR011: Previous move not completed",
    "ERR012: A motor in the coordinate system is open-loop",
    "ERR013: A motor in the coordinate system is not activated",
    "ERR014: No motors in the coordinate system",
    "ERR015: Not pointer to valid program buffer",
    "ERR016: Running improperly structure program (e.g. missing ENDWHILE)",
    "ERR017: Trying to resume after H or Q with motors out of stopped position",
    "ERR018: Attempt to perform phase reference during move, move during phase
        reference, or enabling with phase clock error",
    "ERR019: Illegal position-change command while moves stored in CCBUFFER"
}
```

Decode the errors perhaps returned by the PMAC.

Definition at line 166 of file `lspmac.c`.

5.5.5.59 `pthread_cond_t pmac_queue_cond`

wait for a command to be sent to PMAC before continuing

Definition at line 71 of file `lspmac.c`.

5.5.5.60 `pthread_mutex_t pmac_queue_mutex`

manage access to the pmac command queue

Definition at line 70 of file `lspmac.c`.

5.5.5.61 `pthread_t pmac_thread` `[static]`

our thread to manage access and communication to the pmac

Definition at line 69 of file `lspmac.c`.

5.5.5.62 `struct pollfd pmacfd` `[static]`

our poll structure

Definition at line 72 of file `lspmac.c`.

5.5.5.63 `pmac_cmd_t rr_cmd` `[static]`

Definition at line 159 of file `lspmac.c`.

5.5.5.64 `lspmac_motor_t* scint`

Scintillator Z.

Definition at line 92 of file `lspmac.c`.

5.5.5.65 `lspmac_motor_t*` zoom

Optical zoom.

Definition at line 87 of file `lspmac.c`.

5.6 `lsredis.c` File Reference

Support redis hash synchronization.

```
#include "pgpmac.h"
```

Functions

- void `_lsredis_set_value` (`lsredis_obj_t` *p, char *v)
set_value and setstr helper function p->mutex must be locked before calling
- void `lsredis_set_value` (`lsredis_obj_t` *p, char *fmt,...)
Set the value of a redis object and make it valid.
- int `lsredis_cmpstr` (`lsredis_obj_t` *p, char *s)
- int `lsredis_cmpnstr` (`lsredis_obj_t` *p, char *s, int n)
- int `lsredis_regexec` (const `regex_t` *preg, `lsredis_obj_t` *p, size_t nmatch, `regmatch_t` *pmatch, int eflags)
- char * `lsredis_getstr` (`lsredis_obj_t` *p)
return a copy of the key's string value
- void `lsredis_setstr` (`lsredis_obj_t` *p, char *fmt,...)
Set the value and update redis.
- double `lsredis_getd` (`lsredis_obj_t` *p)
- long int `lsredis_getl` (`lsredis_obj_t` *p)
- char ** `lsredis_get_string_array` (`lsredis_obj_t` *p)
- int `lsredis_getb` (`lsredis_obj_t` *p)
- char `lsredis_getc` (`lsredis_obj_t` *p)
- void `lsredis_hgetCB` (`redisAsyncContext` *ac, void *reply, void *privdata)
- `lsredis_obj_t` * `_lsredis_get_obj` (char *key)
Maybe add a new object Used internally for this module.
- `lsredis_obj_t` * `lsredis_get_obj` (char *fmt,...)
- void `redisDisconnectCB` (const `redisAsyncContext` *ac, int status)
call back in case a redis server becomes disconnected TODO: reconnect
- void `lsredis_addRead` (void *data)
hook to manage read events
- void `lsredis_delRead` (void *data)
hook to manage "don't need to read" events
- void `lsredis_addWrite` (void *data)
hook to manage write events
- void `lsredis_delWrite` (void *data)
hook to manage "don't need to write anymore" events
- void `lsredis_cleanup` (void *data)
hook to clean up TODO: figure out what we are supposed to do here and do it
- void `lsredis_debugCB` (`redisAsyncContext` *ac, void *reply, void *privdata)
Log the reply.
- void `lsredis_subCB` (`redisAsyncContext` *ac, void *reply, void *privdata)
Use the publication to request the new value.
- void `lsredis_maybe_add_key` (char *k)

- void [lsredis_keysCB](#) (redisAsyncContext *ac, void *reply, void *privdata)
Sift through the keys to find ones we like.
- int [lsredis_find_preset](#) (char *base, char *preset_name, double *dval)
- void [lsredis_select](#) (char *re)
set regexp to select variables we are interested in following
- void [lsredis_init](#) (char *pub, char *re, char *head)
Initialize this module, that is, set up the connections.
- void [lsredis_fd_service](#) (struct pollfd *evt)
service the socket requests
- void * [lsredis_worker](#) (void *dummy)
subscribe to changes and service sockets
- void [lsredis_run](#) ()

Variables

- static pthread_t [lsredis_thread](#)
- static [lsredis_obj_t](#) * [lsredis_objs](#) = NULL
- static struct hsearch_data [lsredis_htab](#)
- static pthread_mutex_t [lsredis_objs_mutex](#)
- static pthread_mutex_t [lsredis_ro_mutex](#)
keep from having more than one thread send a rediscommand to the read/only server
- static pthread_mutex_t [lsredis_wr_mutex](#)
keep from having more than one thread send a rediscommand to the write/read server
- static redisAsyncContext * [subac](#)
- static redisAsyncContext * [roac](#)
- static redisAsyncContext * [wrac](#)
- static char * [lsredis_publisher](#) = NULL
- static regex_t [lsredis_key_select_regex](#)
- static char * [lsredis_head](#) = NULL
- static struct pollfd [subfd](#)
- static struct pollfd [rofd](#)
- static struct pollfd [wrfd](#)

5.6.1 Detailed Description

Support redis hash synchronization.

Date

2012

Author

Keith Brister

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Definition in file [lsredis.c](#).

5.6.2 Function Documentation

5.6.2.1 `lsredis_obj_t* lsredis_get_obj(char * key)`

Maybe add a new object Used internally for this module.

Definition at line 308 of file `lsredis.c`.

```

{
    lsredis_obj_t *p;
    regmatch_t pmatch[2];
    int err;
    char *name;
    ENTRY htab_input, *htab_output;

    // Dispense with obviously bad keys straight away
    // unless p->valid == 0 in which case we call HGET first
    //
    // TODO: review logic: is there ever a time when valid is zero for a
    //       preexisting p and HGET has not been called?
    //       If not then we should just return p without checking for validity.
    //
    if( key == NULL || *key == 0 || strchr( key, ' ' ) != NULL ) {
        lslogging_log_message( "_lsredis_get_obj: bad key '%s'",
            " , key == NULL ? "<NULL>" : key );
        return NULL;
    }

    // printf( "_lsredis_get_obj: received key '%s'", key );
    // fflush( stdout );

    pthread_mutex_lock( &lsredis_objs_mutex );
    // If the key is already there then just return it
    //

    htab_input.key = key;
    htab_input.data = NULL;
    errno = 0;
    err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab );

    if( err == 0 )
        p = NULL;
    else
        p = htab_output->data;

    if( p != NULL ) {
        pthread_mutex_unlock( &lsredis_objs_mutex );
        return p;
    } else {
        // make a new one.
        p = calloc( 1, sizeof( lsredis_obj_t ) );
        if( p == NULL ) {
            lslogging_log_message( "_lsredis_get_obj: Out of
                memory" );
            exit( -1 );
        }

        err = regexec( &lsredis_key_select_regex, key, 2,
            pmatch, 0 );
        if( err == 0 && pmatch[1].rm_so != -1 ) {
            p->events_name = strndup( key+pmatch[1].rm_so, pmatch[1].rm_eo
                - pmatch[1].rm_so );
        } else {
            p->events_name = strdup( key );
        }
        if( p->events_name == NULL ) {
            lslogging_log_message( "_lsredis_get_obj: Out of
                memory (%s_name)" );
            exit( -1 );
        }

        pthread_mutex_init( &p->mutex, NULL );
        pthread_cond_init( &p->cond, NULL );
        p->value = NULL;
        p->valid = 0;
        lsevents_send_event( "%s Invalid", p->events_name
            );
        p->wait_for_me = 0;
        p->key = strdup( key );
        p->hits = 0;

        htab_input.key = p->key;
        htab_input.data = p;
    }
}

```

```

    errno = 0;
    err = hsearch_r( htab_input, ENTER, &htab_output, &lsredis_htab
    );
    if( err == 0 ) {
        lslogging_log_message( "_lsredis_get_obj: hsearch
            error on enter.  errno=%d", errno);
    } else {
        lslogging_log_message( "_lsredis_get_obj: added %s",
            key);
    }

    //
    // Shouldn't need the linked list unless we need to rebuild the hash table
    // when, for example, we run out of room.
    // TODO: resize hash table when needed.
    //
    p->next = lsredis_objs;
    lsredis_objs = p;

    pthread_mutex_unlock( &lsredis_objs_mutex);

}
//
// We arrive here with the valid flag lowered.  Go ahead and request the
// latest value.
//
pthread_mutex_lock( &lsredis_ro_mutex);
redisAsyncCommand( roac, lsredis_hgetCB, p, "HGET %s VALUE"
    , key);
pthread_mutex_unlock( &lsredis_ro_mutex);

return p;
}

```

5.6.2.2 void lsredis_set_value(lsredis_obj_t * p, char * v)

set_value and setstr helper function p->mutex must be locked before calling

Definition at line 32 of file Lsredis.c.

```

{

if( strlen(v) >= p->value_length ) {
    if( p->value != NULL)
        free( p->value);
    p->value_length = strlen(v) + 256;
    p->value = calloc( p->value_length, sizeof( char));
    if( p->value == NULL ) {
        lslogging_log_message( "_lsredis_set_value: out of
            memory");
        exit( -1);
    }
}
strcpy( p->value, v);
p->value[p->value_length-1] = 0;
p->dvalue = strtod( p->value, NULL);
p->lvalue = strtol( p->value, NULL, 10);

if( p->avalue != NULL ) {
    char **zz;
    for( zz = p->avalue; *zz != NULL; zz++)
        free( zz);
    free( p->avalue);
}
p->avalue = lspg_array2ptrs( p->value);
switch( *(p->value)) {
    case 'T':
    case 't':
    case 'Y':
    case 'y':
    case '1':
        p->bvalue = 1;
        break;

    case 'F':
    case 'f':
    case 'N':
    case 'n':
    case '0':
        p->bvalue = 0;
        break;
}
}

```

```

        default:
            p->bvalue = -1;           // a little unusual for a null value to
            be -1
        }

    p->cvalue = *(p->value);
    p->valid = 1;

    lsevents_send_event( "%s Valid", p->events_name
    );
}

```

5.6.2.3 void lsredis_addRead (void * data)

hook to mange read events

Definition at line 444 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events |= POLLIN;
}

```

5.6.2.4 void lsredis_addWrite (void * data)

hook to manage write events

Definition at line 460 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events |= POLLOUT;
}

```

5.6.2.5 void lsredis_cleanup (void * data)

hook to clean up TODO: figure out what we are supposed to do here and do it

Definition at line 477 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events &= ~(POLLOUT | POLLIN);
    pfd->fd = -1;
}

```

5.6.2.6 int lsredis_cmpnstr (lsredis_obj_t * p, char * s, int n)

Definition at line 117 of file lsredis.c.

```

{
    int rtn;
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = strcmp( p->value, s, n);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```


5.6.2.7 int Isredis_cmpstr (Isredis_obj_t * *p*, char * *s*)

Definition at line 106 of file Isredis.c.

```

int rtn;
pthread_mutex_lock( &p->mutex);
while( p->valid == 0)
    pthread_cond_wait( &p->cond, &p->mutex);

rtn = strcmp( p->value, s);
pthread_mutex_unlock( &p->mutex);
return rtn;
}

```

5.6.2.8 void Isredis_debugCB (redisAsyncContext * *ac*, void * *reply*, void * *privdata*)

Log the reply.

Definition at line 487 of file Isredis.c.

```

static int indentlevel = 0;
redisReply *r;
int i;

r = (redisReply *)reply;

if( r == NULL) {
    lslogging_log_message( "Null reply. Odd");
    return;
}

switch( r->type) {
case REDIS_REPLY_STATUS:
    lslogging_log_message( "%sSTATUS: %s", indentlevel*4,
        "", r->str);
    break;

case REDIS_REPLY_ERROR:
    lslogging_log_message( "%sERROR: %s", indentlevel*4,
        "", r->str);
    break;

case REDIS_REPLY_INTEGER:
    lslogging_log_message( "%sInteger: %lld", indentlevel
        *4, "", r->integer);
    break;

case REDIS_REPLY_NIL:
    lslogging_log_message( "%s(nil)", indentlevel*4, "");
    break;

case REDIS_REPLY_STRING:
    lslogging_log_message( "%sSTRING: %s", indentlevel*4,
        "", r->str);
    break;

case REDIS_REPLY_ARRAY:
    lslogging_log_message( "%sARRAY of %d elements",
        indentlevel*4, "", (int)r->elements);
    indentlevel++;
    for( i=0; i<r->elements; i++)
        lsredis_debugCB( ac, r->element[i], NULL);
    indentlevel--;
    break;

default:
    lslogging_log_message( "%sUnknown type %d",
        indentlevel*4, "", r->type);
}
}

```

5.6.2.9 void Isredis_delRead (void * *data*)

hook to manage "don't need to read" events

Definition at line 452 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events &= ~POLLIN;
}

```

5.6.2.10 void lsredis_delWrite (void * data)

hook to manage "don't need to write anymore" events

Definition at line 468 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;
    pfd->events &= ~POLLOUT;
}

```

5.6.2.11 void lsredis_fd_service (struct pollfd * evt)

service the socket requests

Definition at line 843 of file lsredis.c.

```

{
    if( evt->fd == subac->c.fd) {
        if( evt->revents & POLLIN)
            redisAsyncHandleRead( subac);
        if( evt->revents & POLLOUT)
            redisAsyncHandleWrite( subac);
    }
    if( evt->fd == roac->c.fd) {
        if( evt->revents & POLLIN)
            redisAsyncHandleRead( roac);
        if( evt->revents & POLLOUT)
            redisAsyncHandleWrite( roac);
    }
    if( evt->fd == wrac->c.fd) {
        if( evt->revents & POLLIN)
            redisAsyncHandleRead( wrac);
        if( evt->revents & POLLOUT)
            redisAsyncHandleWrite( wrac);
    }
}

```

5.6.2.12 int lsredis_find_preset (char * base, char * preset_name, double * dval)

Definition at line 694 of file lsredis.c.

```

{
    char s[512];
    int i;
    int err;
    ENTRY htab_input, *htab_output;
    lsredis_obj_t *p;

    i = 0;
    for( i=0; i<1024; i++) {
        snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.name", lsredis_head
            , base, i);
        s[sizeof(s)-1] = 0;
        htab_input.key = s;
        htab_input.data = NULL;
        err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab)
            ;
        if( err == 0) {
            // We've run out of names to look for: done
            lslogging_log_message( "lsredis_find_preset: no

```

```

    preset for motor %s named '%s'", base, preset_name);
    *dval = 0.0;
    return 0;
}

// Check if we have a match
p = htab_output->data;
if( lsredis_cmpstr( p, preset_name)==0) {
    // got a match, now look for the position
    snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.position", lsredis_head
, base, i);
    s[sizeof(s)-1] = 0;
    htab_input.key = s;
    htab_input.data = NULL;
    err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab
);
    if( err == 0) {
        // Name but not position? odd.
        lslogging_log_message( "lsredis_find_preset:
Error, motor %s preset '%s' has no position defined", base, preset_name);
        *dval = 0.0;
        return 0;
    }
    p = htab_output->data;
    *dval = lsredis_getd( p);
    return 1;
}
}
// How'd we get here?
// did someone really define that many presets? And then looked for one
// that's not there?
*dval = 0;
return 0;
}

```

5.6.2.13 lsredis_obj_t* lsredis_get_obj(char *fmt, ...)

Definition at line 407 of file lsredis.c.

```

{
    lsredis_obj_t *rtn;
    va_list arg_ptr;
    char k[512];
    char *kp;
    int nkp;

    va_start( arg_ptr, fmt);
    vsnprintf( k, sizeof(k)-1, fmt, arg_ptr);
    k[sizeof(k)-1] = 0;
    va_end( arg_ptr);

    nkp = strlen(k) + strlen( lsredis_head) + 16;           // 16
        is overkill. I know. Get over it.
    kp = calloc( nkp, sizeof( char));
    if( kp == NULL) {
        lslogging_log_message( "lsredis_get_obj: Out of memory
");
        exit( -1);
    }

    snprintf( kp, nkp-1, "%s.%s", lsredis_head, k);
    kp[nkp-1] = 0;
    rtn = _lsredis_get_obj( kp);
    free( kp);
    return rtn;
}

```

5.6.2.14 char** lsredis_get_string_array(lsredis_obj_t *p)

Definition at line 236 of file lsredis.c.

```

{
    char **rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);
}

```

```

    rtn = p->avalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.6.2.15 int lsredis_getb(lsredis_obj_t * p)

Definition at line 249 of file lsredis.c.

```

{
    int rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = p->bvalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.6.2.16 char lsredis_getc(lsredis_obj_t * p)

Definition at line 262 of file lsredis.c.

```

{
    int rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = p->cvalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.6.2.17 double lsredis_getd(lsredis_obj_t * p)

Definition at line 210 of file lsredis.c.

```

{
    double rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = p->dvalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.6.2.18 long int lsredis_getl(lsredis_obj_t * p)

Definition at line 223 of file lsredis.c.

```

{
    long int rtn;

    pthread_mutex_lock( &p->mutex);

```

```

while( p->valid == 0)
    pthread_cond_wait( &p->cond, &p->mutex);

rtn = p->lvalue;
pthread_mutex_unlock( &p->mutex);

return rtn;
}

```

5.6.2.19 char* Lsredis_getstr (Lsredis_obj_t * p)

return a copy of the key's string value

Definition at line 141 of file Lsredis.c.

```

{
    char *rtn;

    //
    // Have to use strdup since we cannot guarantee that p->value won't be freed
    // while the caller is still using it
    //
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = strdup(p->value);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```

5.6.2.20 void Lsredis_hgetCB (redisAsyncContext * ac, void * reply, void * privdata)

Definition at line 275 of file Lsredis.c.

```

{
    redisReply *r;
    Lsredis_obj_t *p;

    r = reply;
    p = privdata;

    Lslogging_log_message( "hgetCB: %s %s", p == NULL ? "
    <NULL>" : p->key, r->type == REDIS_REPLY_STRING ? r->str : "Non-string value.
    Why?");

    //
    // Apparently this item does not exist
    // Just set it to an empty string so at least other apps will have the same
    // behaviour as us
    // TODO: figure out a better way to deal with missing key/values
    //
    if( p != NULL && r->type == REDIS_REPLY_NIL) {
        Lsredis_setstr( p, "");
        return;
    }

    if( p != NULL && r->type == REDIS_REPLY_STRING && r->str != NULL) {
        pthread_mutex_lock( &p->mutex);

        _Lsredis_set_value( p, r->str);

        pthread_cond_signal( &p->cond);
        pthread_mutex_unlock( &p->mutex);
    }
}

```

5.6.2.21 void Lsredis_init (char * pub, char * re, char * head)

Initialize this module, that is, set up the connections.

Parameters

<i>pub</i>	Publish under this (unique) name
<i>re</i>	Regular expression to select keys we want to mirror
<i>head</i>	Prepend this (+ a dot) to the beginning of requested objects

Definition at line 775 of file lsredis.c.

```

{

int err;

err = hcreate_r( 8192, &lsredis_hstab);
if( err == 0) {
    lslogging_log_message( "lsredis_init: Cannot create
        hash table. Really bad things are going to happen. hcreate_r returned %d", err);
}

lsredis_head = strdup( head);
lsredis_publisher = strdup( pub);

pthread_mutex_init( &lsredis_objs_mutex, NULL);
pthread_mutex_init( &lsredis_ro_mutex, NULL);
pthread_mutex_init( &lsredis_wr_mutex, NULL);

subac = redisAsyncConnect("127.0.0.1", 6379);
if( subac->err) {
    lslogging_log_message( "Error: %s", subac->errstr
        );
}

subfd.fd          = subac->c.fd;
subfd.events      = 0;
subac->ev.data     = &subfd;
subac->ev.addRead  = lsredis_addRead;
subac->ev.delRead  = lsredis_delRead;
subac->ev.addWrite = lsredis_addWrite;
subac->ev.delWrite = lsredis_delWrite;
subac->ev.cleanup  = lsredis_cleanup;

roac = redisAsyncConnect("127.0.0.1", 6379);
if( roac->err) {
    lslogging_log_message( "Error: %s", roac->errstr);
}

rofd.fd          = roac->c.fd;
rofd.events      = 0;
roac->ev.data     = &rofd;
roac->ev.addRead  = lsredis_addRead;
roac->ev.delRead  = lsredis_delRead;
roac->ev.addWrite = lsredis_addWrite;
roac->ev.delWrite = lsredis_delWrite;
roac->ev.cleanup  = lsredis_cleanup;

wrac = redisAsyncConnect("10.1.0.3", 6379);
if( wrac->err) {
    lslogging_log_message( "Error: %s", wrac->errstr);
}

wrfd.fd          = wrac->c.fd;
wrfd.events      = 0;
wrac->ev.data     = &wrfd;
wrac->ev.addRead  = lsredis_addRead;
wrac->ev.delRead  = lsredis_delRead;
wrac->ev.addWrite = lsredis_addWrite;
wrac->ev.delWrite = lsredis_delWrite;
wrac->ev.cleanup  = lsredis_cleanup;

lsredis_select( re);
}

```

5.6.2.22 void lsredis_keysCB (redisAsyncContext * ac, void * reply, void * privdata)

Sift through the keys to find ones we like.

Add them to our list of followed objects

Definition at line 673 of file lsredis.c.

```

redisReply *r;
int i;

r = reply;
if( r->type != REDIS_REPLY_ARRAY) {
    lslogging_log_message( "lsredis_keysCB: expected
        array...");
    lsredis_debugCB( ac, reply, privdata);
    return;
}

for( i=0; i<r->elements; i++) {
    if( r->element[i]->type != REDIS_REPLY_STRING) {
        lslogging_log_message( "lsredis_keysCB: expected
            string...");
        lsredis_debugCB( ac, r->element[i], privdata);
    } else {
        lsredis_maybe_add_key( r->element[i]->str);
    }
}
}

```

5.6.2.23 void lsredis_maybe_add_key (char * k)

Definition at line 665 of file Lsredis.c.

```

{
    if( regexec( &lsredis_key_select_regex, k, 0, NULL, 0
        ) == 0) {
        _lsredis_get_obj( k);
    }
}

```

5.6.2.24 int lsredis_regexec (const regex_t * preg, lsredis_obj_t * p, size_t nmatch, regmatch_t * pmatch, int eflags)

Definition at line 128 of file Lsredis.c.

```

{
    int rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = regexec( preg, p->value, nmatch, pmatch, eflags);

    pthread_mutex_unlock( &p->mutex);
}

```

5.6.2.25 void lsredis_run ()

Definition at line 916 of file Lsredis.c.

```

{
    pthread_create( &lsredis_thread, NULL, lsredis_worker
        , NULL);
}

```

5.6.2.26 void lsredis_select (char * re)

set regexp to select variables we are interested in following

Note that redis only supports glob matching while we'd prefer something a tad more useful. See <http://xkcd.com/208>

Definition at line 749 of file Lsredis.c.

```

    {
        int err;
        char *errmsg;
        int nerrmsg;

        err = regcomp( &lsredis_key_select_regex, re,
            REG_EXTENDED);
        if( err != 0) {
            nerrmsg = regerror( err, &lsredis_key_select_regex,
                NULL, 0);
            if( nerrmsg > 0) {
                errmsg = calloc( nerrmsg, sizeof( char));
                nerrmsg = regerror( err, &lsredis_key_select_regex
                    , errmsg, nerrmsg);
                lslogging_log_message( "lsredis_select: %s", errmsg)
                ;
                free( errmsg);
            }
        }

        pthread_mutex_lock( &lsredis_ro_mutex);
        redisAsyncCommand( roac, lsredis_keysCB, NULL, "KEYS *");
        pthread_mutex_unlock( &lsredis_ro_mutex);
    }
}

```

5.6.2.27 void lsredis_set_value(lsredis_obj_t *p, char *fmt, ...)

Set the value of a redis object and make it valid.

Called by mgetCB to set the value as it is in redis Maybe TODO: we've arbitrarily set the maximum size of a value here. Although I cannot imagine needed bigger values it would not be a big deal to enable it.

Definition at line 88 of file lsredis.c.

```

    {
        va_list arg_ptr;
        char v[512];

        va_start( arg_ptr, fmt);
        vsnprintf( v, sizeof(v)-1, fmt, arg_ptr);
        va_end( arg_ptr);

        v[sizeof(v)-1] = 0;

        pthread_mutex_lock( &p->mutex);

        _lsredis_set_value( p, v);

        pthread_cond_signal( &p->cond);
        pthread_mutex_unlock( &p->mutex);
    }
}

```

5.6.2.28 void lsredis_setstr(lsredis_obj_t *p, char *fmt, ...)

Set the value and update redis.

Note that lsredis_set_value sets the value based on redis while here we set redis based on the value Arbitrary maximum string length set here. TODO: Probably this limit should be removed at some point.

redisAsyncCommandArgv used instead of redisAsyncCommand 'cause it's easier (and possible) to deal with strings that would otherwise cause hiredis to emit a bad command, like those containing spaces. < invalidate the current value: set_value will fix this and signal waiting threads

< up the count of times we need to see ourselves published before we start listening to others again

< key is "immutable" (not really a C feature). In any case no one is going to be changing it so it's cool to read it without mutex protection.

< redisAsyncCommandArgv shouldn't need to access this after it's made up it's packet (before it returns) so we should be OK with this location disappearing soon.

Definition at line 166 of file lsredis.c.


```

{
    va_list arg_ptr;
    char v[512];
    char *argv[4];

    va_start( arg_ptr, fmt);
    vsnprintf( v, sizeof(v)-1, fmt, arg_ptr);
    v[sizeof(v)-1] = 0;
    va_end( arg_ptr);

    pthread_mutex_lock( &p->mutex);

    if( p->valid && strcmp( v, p->value) == 0) {
        // nothing to do
        pthread_mutex_unlock( &p->mutex);
        return;
    }

    p->valid = 0;
    lsevents_send_event( "%s Invalid", p->events_name
    );
    p->wait_for_me++;

    argv[0] = "HSET";
    argv[1] = p->key;
    argv[2] = "VALUE";
    argv[3] = v;

    pthread_mutex_lock( &lsredis_wr_mutex);
    redisAsyncCommand( wrac, NULL, NULL, "MULTI");
    redisAsyncCommandArgv( wrac, NULL, NULL, 4, (const char **)argv, NULL);

    redisAsyncCommand( wrac, NULL, NULL, "PUBLISH %s %s", lsredis_publisher
    , p->key);
    redisAsyncCommand( wrac, NULL, NULL, "EXEC");
    pthread_mutex_unlock( &lsredis_wr_mutex);

    // Assume redis will take exactly the value we sent it
    //
    _lsredis_set_value( p, v);
    pthread_cond_signal( &p->cond);
    pthread_mutex_unlock( &p->mutex);
}

```

5.6.2.29 void Lsredis.subCB (redisAsyncContext * ac, void * reply, void * privdata)

Use the publication to request the new value.

Definition at line 539 of file Lsredis.c.

```

{
    redisReply *r;
    lsredis_obj_t *p, *last, *last2;
    char *k;
    char *publisher;
    ENTRY htab_input, *htab_output;
    int err;

    r = (redisReply *)reply;

    // Ignore our psubscribe reply
    //
    if( r->type == REDIS_REPLY_ARRAY && r->elements == 3 && r->element[0]->type
    == REDIS_REPLY_STRING && strcmp( r->element[0]->str, "psubscribe")==0)
        return;

    // But log other stuff we don't understand
    //
    if( r->type != REDIS_REPLY_ARRAY ||
        r->elements != 4 ||
        r->element[3]->type != REDIS_REPLY_STRING ||
        r->element[2]->type != REDIS_REPLY_STRING) {

        lslogging_log_message( "lsredis_subCB: unexpected
        reply");
        lsredis_debugCB( ac, reply, privdata);
        return;
    }

    //
    // Ignore obvious junk

```

```

//
k = r->element[3]->str;

if( k == NULL || *k == 0)
    return;

//
// see if we care
//
if( regexec( &lsredis_key_select_regex, k, 0, NULL, 0
) == 0) {
    //
    // We should know about this one
    //
    pthread_mutex_lock( &lsredis_objs_mutex);

    htab_input.key = k;
    htab_input.data = NULL;

    errno = 0;
    err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab)
    ;
    if( err == 0 && errno == ESRCH)
        p = NULL;
    else
        p = htab_output->data;

    /*
    last = NULL;
    last2 = NULL;
    for( p=lsredis_objs; p != NULL; p = p->next) {
        if( strcmp( p->key, k) == 0) {
            p->hits++;
            //
            // Maybe reorder our list so the most often updated objects
            // eventually bump up to the beginning of the list.
            // That "hits+4" keeps us from oscillating when objects are accessed
            // equally
            //
            if( last != NULL && last->hits < p->hits+4) {
                last->next = p->next;
                p->next = last;
                if( last2 != NULL)
                    last2->next = p;
                else
                    lsredis_objs = p;
            }
            break;
        }
        last2 = last;
        last = p;
    }
    */

    pthread_mutex_unlock( &lsredis_objs_mutex);

    if( p == NULL) {
        //
        // Regardless of who the publisher is, apparently there is a key we've
        // not seen before
        //
        _lsredis_get_obj( k);
    } else {
        // Look who's talk'n
        publisher = r->element[2]->str;

        pthread_mutex_lock( &p->mutex);
        if( p->wait_for_me) {
            //
            // see if we are done waiting
            //
            if( strcmp( publisher, lsredis_publisher)==0)
                p->wait_for_me--;

            pthread_mutex_unlock( &p->mutex);
            //
            // Don't get a new value, either we set it last or we are still waiting
            // for redis to report
            // our publication
            //
            return;
        }

        // Here we know our value is out of date
        //
        p->valid = 0;
    }
}

```

```

lsredis_send_event( "%s Invalid", p->events_name
);
pthread_mutex_unlock( &p->mutex);

//
// We shouldn't get here if wait_for_me is zero and we are the publisher.
// If somehow we did (ie we did an hset with out incrementing wait_for_me
// or if we published too many times), it shouldn't hurt to get the value again.
//
pthread_mutex_lock( &lsredis_ro_mutex);
redisAsyncCommand( roac, lsredis_hgetCB, p, "HGET %s
VALUE", k);
pthread_mutex_unlock( &lsredis_ro_mutex);
}
}
}

```

5.6.2.30 void* lsredis_worker (void * dummy)

subscribe to changes and service sockets

< array of pollfd's for the poll function, one entry per connection

< number of active elements in fda

< poll timeout, in millisecs (of course)

Definition at line 867 of file Lsredis.c.

```

{
static struct pollfd fda[3];
static int nfda = 0;
static int poll_timeout_ms = -1;
int pollrtn;
int i;

pthread_mutex_lock( &lsredis_ro_mutex);
if( redisAsyncCommand( subac, lsredis_subCB, NULL, "
PSUBSCRIBE REDIS_KV_CONNECTOR UI*" ) == REDIS_ERR) {
    lslogging_log_message( "Error sending PSUBSCRIBE
command");
}
pthread_mutex_unlock( &lsredis_ro_mutex);

while(1) {
    nfda = 0;

    if( subfd.fd != -1) {
        fda[nfda].fd = subfd.fd;
        fda[nfda].events = subfd.events;
        fda[nfda].revents = 0;
        nfda++;
    }

    if( rofd.fd != -1) {
        fda[nfda].fd = rofd.fd;
        fda[nfda].events = rofd.events;
        fda[nfda].revents = 0;
        nfda++;
    }

    if( wrfd.fd != -1) {
        fda[nfda].fd = wrfd.fd;
        fda[nfda].events = wrfd.events;
        fda[nfda].revents = 0;
        nfda++;
    }

    pollrtn = poll( fda, nfda, poll_timeout_ms);

    for( i=0; i<nfda; i++) {
        if( fda[i].revents) {
            lsredis_fd_service( &(fda[i]));
        }
    }
}
}

```

5.6.2.31 void redisDisconnectCB (const redisAsyncContext * *ac*, int *status*)

call back in case a redis server becomes disconnected TODO: reconnect

Definition at line 436 of file lsredis.c.

```

{
    if( status != REDIS_OK) {
        lslogging_log_message( "lsredis: Disconnected with
            status %d", status);
    }
}

```

5.6.3 Variable Documentation

5.6.3.1 char* lsredis.head = NULL [static]

Definition at line 23 of file lsredis.c.

5.6.3.2 struct hsearch_data lsredis.htab [static]

Definition at line 12 of file lsredis.c.

5.6.3.3 regex_t lsredis.key_select_regex [static]

Definition at line 22 of file lsredis.c.

5.6.3.4 lsredis_obj_t* lsredis.objs = NULL [static]

Definition at line 11 of file lsredis.c.

5.6.3.5 pthread_mutex_t lsredis.objs_mutex [static]

Definition at line 13 of file lsredis.c.

5.6.3.6 char* lsredis.publisher = NULL [static]

Definition at line 21 of file lsredis.c.

5.6.3.7 pthread_mutex_t lsredis.ro_mutex [static]

keep from having more than one thread send a rediscommand to the read/only server

Definition at line 14 of file lsredis.c.

5.6.3.8 pthread_t lsredis.thread [static]

Definition at line 9 of file lsredis.c.

5.6.3.9 pthread_mutex_t lsredis.wr_mutex [static]

keep from having more than one thread send a rediscommand to the write/read server

Definition at line 15 of file lsredis.c.

5.6.3.10 `redisAsyncContext* roac` `[static]`

Definition at line 18 of file lsredis.c.

5.6.3.11 `struct pollfd rofd` `[static]`

Definition at line 26 of file lsredis.c.

5.6.3.12 `redisAsyncContext* subac` `[static]`

Definition at line 17 of file lsredis.c.

5.6.3.13 `struct pollfd subfd` `[static]`

Definition at line 25 of file lsredis.c.

5.6.3.14 `redisAsyncContext* wrac` `[static]`

Definition at line 19 of file lsredis.c.

5.6.3.15 `struct pollfd wrfd` `[static]`

Definition at line 27 of file lsredis.c.

5.7 Istimer.c File Reference

Support for delayed and periodic events.

```
#include "pgpmac.h"
```

Data Structures

- struct [lstimer_list_struct](#)
Everything we need to know about a timer.

Macros

- #define [LSTIMER_LIST_LENGTH](#) 1024
We'll allow this many timers. This should be way more than enough.
- #define [LSTIMER_RESOLUTION_NSECS](#) 100000
times within this amount in the future are considered "now" and the events should be called

Typedefs

- typedef struct [lstimer_list_struct](#) [lstimer_list_t](#)
Everything we need to know about a timer.

Functions

- void [lstimer_add_timer](#) (char *event, int shots, unsigned long int secs, unsigned long int nsecs)
Create a timer.
- static void [service_timers](#) ()
Send events that are past due, due, or just about to be due.
- static void [handler](#) (int sig, siginfo_t *si, void *dummy)
Service the signal.
- static void * [lstimer_worker](#) (void *dummy)
Our worker.
- void [lstimer_init](#) ()
Initialize the timer list and pthread stuff.
- void [lstimer_run](#) ()
Start up our thread.

Variables

- static int [lstimer_active_timers](#) = 0
count of the number timers we are tracking
- static [lstimer_list_t](#) [lstimer_list](#) [[LSTIMER_LIST_LENGTH](#)]
Our timer list.
- static pthread_t [lstimer_thread](#)
the timer thread
- static pthread_mutex_t [lstimer_mutex](#)
protect the timer list
- static pthread_cond_t [lstimer_cond](#)
allows us to be idle when there is nothing to do
- static timer_t [lstimer_timerid](#)
our real time timer
- static int [new_timer](#) = 0
indicate that a new timer exists and a call to service_timers is required

5.7.1 Detailed Description

Support for delayed and periodic events.

Date

2012

Author

Keith Brister

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Definition in file [lstimer.c](#).

5.7.2 Macro Definition Documentation

5.7.2.1 `#define LSTIMER_LIST_LENGTH 1024`

We'll allow this many timers. This should be way more than enough.

Definition at line 11 of file ltimer.c.

5.7.2.2 `#define LSTIMER_RESOLUTION_NSECS 100000`

times within this amount in the future are considered "now" and the events should be called

Definition at line 16 of file ltimer.c.

5.7.3 Typedef Documentation

5.7.3.1 `typedef struct ltimer_list_struct ltimer_list_t`

Everything we need to know about a timer.

5.7.4 Function Documentation

5.7.4.1 `static void handler (int sig, siginfo_t * si, void * dummy) [static]`

Service the signal.

Definition at line 174 of file ltimer.c.

```

{
    pthread_mutex_lock( &ltimer_mutex);
    service_timers();
    pthread_mutex_unlock( &ltimer_mutex);
}

```

5.7.4.2 `void ltimer_add_timer (char * event, int shots, unsigned long int secs, unsigned long int nsecs)`

Create a timer.

Parameters

<i>event</i>	Name of the event to send when the timer goes off
<i>shots</i>	Number of times to run. 0 means never, -1 means forever
<i>secs</i>	Number of seconds to wait
<i>nsecs</i>	Number of nano-seconds to run in addition to secs

Definition at line 50 of file ltimer.c.

```

{
    int i;
    struct timespec now;

    // Time we were called. Delay is based on call time, not queued time
    //
    clock_gettime( CLOCK_REALTIME, &now);

    pthread_mutex_lock( &ltimer_mutex);

    for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
        if( ltimer_list[i].shots == 0)

```

```

        break;
    }

    if( i == LSTIMER_LIST_LENGTH) {
        pthread_mutex_unlock( &lstimer_mutex);

        lslogging_log_message( "lstimer_add_timer: out of
            timers for event: %s, shots: %d, secs: %u, nsecs: %u",
                                event, shots, secs, nsecs);
        return;
    }

    strncpy( lstimer_list[i].event, event, LSEVENTS_EVENT_LENGTH
        - 1);
    lstimer_list[i].event[LSEVENTS_EVENT_LENGTH
        - 1] = 0;
    lstimer_list[i].shots      = shots;
    lstimer_list[i].delay_secs = secs;
    lstimer_list[i].delay_nsecs = nsecs;

    lstimer_list[i].next_secs      = secs + now.tv_sec + (
        now.tv_nsec + nsecs) / 1000000000;
    lstimer_list[i].next_nsecs     = (now.tv_nsec + nsecs)
        % 1000000000;
    lstimer_list[i].last_secs      = 0;
    lstimer_list[i].last_nsecs     = 0;

    lstimer_list[i].ncalls         = 0;
    lstimer_list[i].init_secs      = now.tv_sec;
    lstimer_list[i].init_nsecs     = now.tv_nsec;

    if( shots != 0) {
        lstimer_active_timers++;
        new_timer++;
    }

    pthread_cond_signal( &lstimer_cond);
    pthread_mutex_unlock( &lstimer_mutex);
}

```

5.7.4.3 void lstimer_init ()

Initialize the timer list and pthread stuff.

Definition at line 262 of file lstimer.c.

```

    {
        int i;

        for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
            lstimer_list[i].shots = 0;
        }

        pthread_mutex_init( &lstimer_mutex, NULL);
        pthread_cond_init( &lstimer_cond, NULL);
    }

```

5.7.4.4 void lstimer_run ()

Start up our thread.

Definition at line 276 of file lstimer.c.

```

    {
        pthread_create( &lstimer_thread, NULL, lstimer_worker
            , NULL);
    }

```

5.7.4.5 static void* lstimer_worker (void * dummy) [static]

Our worker.

The main loop runs when a new timer is added. The service routine deals with maintenance.

Parameters

in	<i>dummy</i>	required by protocol
----	--------------	----------------------

Definition at line 184 of file ltimer.c.

```

    {
        int
            i,
            known_timers;

        struct timespec now;

        struct sigevent sev;
        struct sigaction sa;
        sigset_t mask;

        // See example at
        // http://www.kernel.org/doc/man-pages/online/pages/man2/timer\_create.2.html
        //

        // Set up handler
        //
        sa.sa_flags = SA_SIGINFO;
        sa.sa_sigaction = handler;
        sigemptyset(&sa.sa_mask);
        if (sigaction(SIGRTMIN, &sa, NULL) == -1) {
            lslogging_log_message("ltimer_worker: sigaction
                                failed");
            exit(-1);
        }

        // Create the timer
        //
        sev.sigev_notify = SIGEV_SIGNAL;
        sev.sigev_signo = SIGRTMIN;
        sev.sigev_value.sival_ptr = &ltimer_timerid;
        timer_create(CLOCK_REALTIME, &sev, &ltimer_timerid);

        // Block timer signal for now since we really
        // want to be sure we do not own a lock on the timer mutex
        // while servicing the signal
        //
        sigemptyset(&mask);
        sigaddset(&mask, SIGRTMIN);

        known_timers = 0;

        while( 1 ) {
            pthread_mutex_lock( &ltimer_mutex);

            while( new_timer == 0 )
                pthread_cond_wait( &ltimer_cond, &ltimer_mutex
                                );

            // ignore signals so we don't service the signal while we are already in
            // the
            // service routine
            //
            sigprocmask( SIG_SETMASK, &mask, NULL);

            //
            // Setting up the timer interval is in the handler
            // so just call it
            //
            service_timers();

            //
            // Reset our flag
            //
            new_timer = 0;

            pthread_mutex_unlock( &ltimer_mutex);

            // Let the signals rain down
            //
            sigprocmask( SIG_UNBLOCK, &mask, NULL);
        }
    }

```

5.7.4.6 static void service_timers () [static]

Send events that are past due, due, or just about to be due.

Definition at line 102 of file lstimer.c.

```

    {
        int
            i,
            found_active;

        lstimer_list_t *p;
        struct timespec now, then, soonest;
        struct itimerspec its;

        //
        // Did I remind you not to let this thread own the lstimer mutex outside of
        // this
        // service routine when SIGRTMIN is active?
        //
        // Call with lstimer_mutex locked

        clock_gettime( CLOCK_REALTIME, &now);
        //
        // Project a tad into the future
        then.tv_sec = now.tv_sec + (now.tv_nsec + LSTIMER_RESOLUTION_NSECS
            ) / 1000000000;
        then.tv_nsec = (now.tv_nsec + LSTIMER_RESOLUTION_NSECS
            ) % 1000000000;

        found_active = 0;
        for( i=0; i<lstimer_active_timers; i++) {
            p = &(lstimer_list[i]);
            if( p->shots != 0) {
                found_active++;
                if( p->next_secs < then.tv_sec || (p->next_secs ==
                    then.tv_sec && p->next_nsecs <= then.tv_nsec)) {
                    lsevents_send_event( p->event);
                    //
                    // After sending the event, compute the next time we need to do this
                    //
                    p->last_secs = now.tv_sec;
                    p->last_nsecs = now.tv_nsec;
                    p->ncalls++;
                    //
                    // Decrement non-infinite loops
                    if( p->shots != -1)
                        p->shots--;
                    if( p->shots == 0) {
                        //
                        // Take this timer out of the mix
                        lstimer_active_timers--;
                    } else {
                        p->next_secs = p->init_secs + (p->ncalls+1)
                        * p->delay_secs + (p->init_nsecs + (p->ncalls+1)*p->
                        delay_nsecs)/1000000000;
                        p->next_nsecs = (p->init_nsecs + (p->ncalls
                        +1)*p->delay_nsecs) % 1000000000;
                    }
                }

                if( found_active == 1) {
                    soonest.tv_sec = p->next_secs;
                    soonest.tv_nsec = p->next_nsecs;
                } else {
                    if( soonest.tv_sec > p->next_secs || (soonest.tv_sec == p->
                    next_secs && soonest.tv_nsec > p->next_nsecs)) {
                        soonest.tv_sec = p->next_secs;
                        soonest.tv_nsec = p->next_nsecs;
                    }
                }
            }
        }

        if( soonest.tv_sec != 0) {
            its.it_value.tv_sec = soonest.tv_sec;
            its.it_value.tv_nsec = soonest.tv_nsec;
            its.it_interval.tv_sec = 0;
            its.it_interval.tv_nsec = 0;
            timer_settime( lstimer_timerid, TIMER_ABSTIME, &its, NULL);
        }
    }
}

```

5.7.5 Variable Documentation

5.7.5.1 `int ltimer_active_timers = 0` `[static]`

count of the number timers we are tracking

Definition at line 18 of file ltimer.c.

5.7.5.2 `pthread_cond_t ltimer_cond` `[static]`

allows us to be idle when there is nothing to do

Definition at line 40 of file ltimer.c.

5.7.5.3 `ltimer_list_t ltimer_list[LSTIMER_LIST_LENGTH]` `[static]`

Our timer list.

Definition at line 36 of file ltimer.c.

5.7.5.4 `pthread_mutex_t ltimer_mutex` `[static]`

protect the timer list

Definition at line 39 of file ltimer.c.

5.7.5.5 `pthread_t ltimer_thread` `[static]`

the timer thread

Definition at line 38 of file ltimer.c.

5.7.5.6 `timer_t ltimer_timerid` `[static]`

our real time timer

Definition at line 41 of file ltimer.c.

5.7.5.7 `int new_timer = 0` `[static]`

indicate that a new timer exists and a call to service_timers is required

Definition at line 42 of file ltimer.c.

5.8 md2cmds.c File Reference

Implements commands to run the md2 diffractometer attached to a PMAC controlled by postgresql.

```
#include "pgpmac.h"
```

Functions

- void [md2cmds_transfer](#) ()

Transfer a sample TODO: Implement.

- void [md2cmds_moveAbs](#) (const char *ccmd)
Move a motor to the position requested.
- void [md2cmds_phase_change](#) (const char *ccmd)
Move md2 devices to a preconfigured state.
- void [md2cmds_mvcenter_prep](#) ()
Sets up a centering table and alignment table move Ensures that when we issue the move command that we can detect that the move happened.
- double [md2cmds_prep_motion](#) (lspmac_motor_t *mp, double pos)
- void [md2cmds_mvcenter_move](#) (double cx, double cy, double ax, double ay, double az)
Move the centering and alignment tables.
- void [md2cmds_mvcenter_wait](#) ()
Wait for the centering and alignment tables to stop moving.
- void [md2cmds_maybe_done_moving_cb](#) (char *event)
Track how many motors are moving.
- void [md2cmds_collect](#) ()
Collect some data.
- void [md2cmds_rotate](#) ()
Spin 360 and make a video (recenter first, maybe)
- void [md2cmds_rotate_cb](#) (char *event)
Tell the database about the time we went through omega=zero.
- void [md2cmds_maybe_rotate_done_cb](#) (char *event)
Now that we are done with the 360 rotation lets rehome right quick.
- void [md2cmds_set_scale_cb](#) (char *event)
Fix up xscale and yscale when zoom changes.
- void [md2cmds_center](#) ()
Move centering and alignment tables as requested TODO: Implement.
- void * [md2cmds_worker](#) (void *dummy)
Our worker thread.
- void [md2cmds_init](#) ()
Initialize the md2cmds module.
- void [md2cmds_run](#) ()
Start up the thread.

Variables

- pthread_cond_t [md2cmds_cond](#)
condition to signal when it's time to run an md2 command
- pthread_mutex_t [md2cmds_mutex](#)
mutex for the condition
- pthread_cond_t [md2cmds_moving_cond](#)
coordinate call and response
- pthread_mutex_t [md2cmds_moving_mutex](#)
message passing between md2cmds and pg
- [pmac_cmd_queue_t](#) * [md2cmds_moving_pq](#)
pmac queue item from last command
- int [md2cmds_moving_count](#) = 0
- char [md2cmds_cmd](#) [MD2CMDS_CMD_LENGTH]
our command;
- static pthread_t [md2cmds_thread](#)
- static int [rotating](#) = 0
flag: when omega is in position after a rotate we want to re-home omega

5.8.1 Detailed Description

Implements commands to run the md2 diffractometer attached to a PMAC controlled by postgresql.

Date

2012

Author

Keith Brister

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Definition in file [md2cmds.c](#).

5.8.2 Function Documentation

5.8.2.1 void md2cmds.center ()

Move centering and alignment tables as requested TODO: Implement.

Definition at line 739 of file md2cmds.c.

```

    {
}

```

5.8.2.2 void md2cmds.collect ()

Collect some data.

Definition at line 422 of file md2cmds.c.

```

    {
long long skey;
double p170; // start cnts
double p171; // end cnts
double p173; // omega velocity cnts/msec
double p175; // acceleration time (msec)
double p180; // exposure time (msec)
int center_request;
double u2c;
double max_accel;

u2c      = lsredis_getd( omega->u2c);
max_accel = lsredis_getd( omega->max_accel);

//
// reset shutter has opened flag
//
lspmac_SockSendline( "P3001=0 P3002=0");

while( 1) {
    lspg_nextshot_call();

    //
    // This is where we'd tell the md2 to move the organs into position
    //
    lspg_nextshot_wait();

    if( lspg_nextshot.no_rows_returned) {
        lspg_nextshot_done();
        break;
    }
}

```

```

skey = lspg_nextshot.skey;
lspg_query_push( NULL, "SELECT px.shots_set_state(%lld,
    'Preparing')", skey);

center_request = 0;
if( lspg_nextshot.active) {
    if(
        (fabs( lspg_nextshot.cx - cenx->position) >
         0.1) ||
        (fabs( lspg_nextshot.cy - ceny->position) >
         0.1) ||
        (fabs( lspg_nextshot.ax - alignx->position
         ) > 0.1) ||
        (fabs( lspg_nextshot.ay - aligny->position
         ) > 0.1) ||
        (fabs( lspg_nextshot.az - alignz->position
         ) > 0.1)) {

        center_request = 1;
        md2cmds_mvcenter_prep();
        md2cmds_mvcenter_move( lspg_nextshot.
        cx, lspg_nextshot.cy, lspg_nextshot.ax,
        lspg_nextshot.ay, lspg_nextshot.az);
    }

    if( !lspg_nextshot.dsphi_isnull) {
        lspmac_moveabs_queue( phi, lspg_nextshot
        .dsphi);
    }

    if( !lspg_nextshot.dskappa_isnull) {
        lspmac_moveabs_queue( kappa, lspg_nextshot
        .dskappa);
    }

    //
    // Wait for all those motors to stop
    //
    if( center_request) {
        md2cmds_mvcenter_wait();
    }

    if( !lspg_nextshot.dsphi_isnull) {
        lspmac_moveabs_wait( phi);
    }

    if( !lspg_nextshot.dskappa_isnull) {
        lspmac_moveabs_wait( kappa);
    }

    //
    // Calculate the parameters we'll need to run the scan
    //
    p180 = lspg_nextshot.dsexp * 1000.0;
    p170 = u2c * lspg_nextshot.sstart;
    //    p171 = u2c * ( lspg_nextshot.sstart + lspg_nextshot.dsowidth);
    p171 = u2c * lspg_nextshot.dsowidth;
    p173 = fabs(p180) < 1.e-4 ? 0.0 : u2c * lspg_nextshot.dsowidth
    / p180;
    p175 = p173/max_accel;

    //
    // free up access to nextshot
    //
    lspg_nextshot_done();

    //
    // prepare the database and detector to expose
    // On exit we own the diffractometer lock and
    // have checked that all is OK with the detector
    //
    lspg_seq_run_prep_all( skey,
        kappa->position,
        phi->position,
        cenx->position,
        ceny->position,
        alignx->position,
        aligny->position,
        alignz->position
    );

    //

```

```

// make sure our has opened flag is down
// wait for the p3001=0 command to be noticed
//
pthread_mutex_lock( &lspmac_shutter_mutex);
if( lspmac_shutter_has_opened == 1)
    pthread_cond_wait( &lspmac_shutter_cond, &
        lspmac_shutter_mutex);
pthread_mutex_unlock( &lspmac_shutter_mutex);

//
// Start the exposure
//
lspmac_SockSendline( "P170=%1f P171=%1f P173=%1f
    P174=0 P175=%1f P176=0 P177=1 P178=0 P180=%1f M431=1 &1B131R",
        p170,      p171,      p173,      p175,
        p180);

//
// wait for the shutter to open
//
pthread_mutex_lock( &lspmac_shutter_mutex);
if( lspmac_shutter_has_opened == 0)
    pthread_cond_wait( &lspmac_shutter_cond, &
        lspmac_shutter_mutex);

//
// wait for the shutter to close
//
if( lspmac_shutter_state == 1)
    pthread_cond_wait( &lspmac_shutter_cond, &
        lspmac_shutter_mutex);
pthread_mutex_unlock( &lspmac_shutter_mutex);

lspg_query_push( NULL, "SELECT px.unlock_diffractionmeter()");

lspg_query_push( NULL, "SELECT px.shots_set_state(%lld,
    'Writing')", skey);

//
// reset shutter has opened flag
//
lspmac_SockSendline( "P3001=0");
//
// TODO:
// wait for omega to stop moving then position it for the next frame
//

if( !lspg_nextshot.active2_isnull &&
    lspg_nextshot.active2) {
    if(
        (fabs( lspg_nextshot.cx2 - cenx->position)
        > 0.1) ||
        (fabs( lspg_nextshot.cy2 - ceny->position)
        > 0.1) ||
        (fabs( lspg_nextshot.ax2 - alignx->position)
        > 0.1) ||
        (fabs( lspg_nextshot.ay2 - aligny->position)
        > 0.1) ||
        (fabs( lspg_nextshot.az2 - alignz->position)
        > 0.1)) {
        center_request = 1;
        md2cmds_mvcenter_prep();
        md2cmds_mvcenter_move( lspg_nextshot.
        cx, lspg_nextshot.cy, lspg_nextshot.ax,
        lspg_nextshot.ay, lspg_nextshot.az);
        md2cmds_mvcenter_wait();
        lspmac_moveabs_wait( cenx);
        lspmac_moveabs_wait( ceny);
        lspmac_moveabs_wait( alignx);
        lspmac_moveabs_wait( aligny);
        lspmac_moveabs_wait( alignz);
    }
}
}
}

```

5.8.2.3 void md2cmds_init ()

Initialize the md2cmds module.

Definition at line 780 of file md2cmds.c.

```

    {
        memset( md2cmds_cmd, 0, sizeof( md2cmds_cmd));

        pthread_mutex_init( &md2cmds_mutex, NULL);
        pthread_cond_init( &md2cmds_cond, NULL);

        pthread_mutex_init( &md2cmds_moving_mutex, NULL);
        pthread_cond_init( &md2cmds_moving_cond, NULL);
    }

```

5.8.2.4 void md2cmds_maybe_done_moving.cb (char * event)

Track how many motors are moving.

Definition at line 394 of file md2cmds.c.

```

    {

        pthread_mutex_lock( &md2cmds_moving_mutex);
        if( strstr( event, "Moving") != NULL) {
            //
            // -1 is a flag indicating we're expecting some action
            //
            if( md2cmds_moving_count == -1)
                md2cmds_moving_count = 1;
            else
                md2cmds_moving_count++;
        } else {
            //
            // Shouldn't need this but just in case a move was not finished before
            // we're ready
            // this might take care of the problem
            //
            if( md2cmds_moving_count > 0)
                md2cmds_moving_count--;
        }

        if( md2cmds_moving_count == 0)
            pthread_cond_signal( &md2cmds_moving_cond);
        pthread_mutex_unlock( &md2cmds_moving_mutex);
    }

```

5.8.2.5 void md2cmds_maybe_rotate_done.cb (char * event)

Now that we are done with the 360 rotation lets rehome right quick.

Definition at line 718 of file md2cmds.c.

```

    {
        if( rotating) {
            rotating = 0;
            lspmac_hommel_queue( omega);
        }
    }

```

5.8.2.6 void md2cmds_moveAbs (const char * ccmd)

Move a motor to the position requested.

Parameters

in	<i>ccmd</i>	The full command string to parse, ie, "moveAbs omega 180"
----	-------------	---

Definition at line 35 of file md2cmds.c.

```

    {
char *cmd;
char *ignore;
char *ptr;
char *mtr;
char *pos;
double fpos;
char *endptr;
lspmac_motor_t *mp;
int i;

// ignore nothing
if( ccmd == NULL || *ccmd == 0 ) {
    return;
}

// operate on a copy of the string since strtok_r will modify its argument
//
cmd = strdup( ccmd );

// Parse the command string
//
ignore = strtok_r( cmd, " ", &ptr );
if( ignore == NULL ) {
    lslogging_log_message( "md2cmds_moveAbs: ignoring
        blank command '%s'", cmd );
    free( cmd );
    return;
}

// The first string should be "moveAbs" cause that's how we got here.
// Toss it.

mtr = strtok_r( NULL, " ", &ptr );
if( mtr == NULL ) {
    lslogging_log_message( "md2cmds moveAbs error: missing
        motor name" );
    free( cmd );
    return;
}

mp = NULL;
for( i=0; i<lspmac_nmotors; i++) {
    if( strcmp( lspmac_motors[i].name, mtr ) == 0 ) {
        mp = &(lspmac_motors[i]);
        break;
    }
}
if( mp == NULL ) {
    lslogging_log_message( "md2cmds moveAbs error: cannot
        find motor %s", mtr );
    free( cmd );
    return;
}

pos = strtok_r( NULL, " ", &ptr );
if( pos == NULL ) {
    lslogging_log_message( "md2cmds moveAbs error: missing
        position" );
    free( cmd );
    return;
}

fpos = strtod( pos, &endptr );
if( pos == endptr ) {
    //
    // Maybe we have a preset. Give it a whirl
    // In any case we are done here.
    //
    lspmac_move_preset_queue( mp, pos );
    free( cmd );
    return;
}

if( mp != NULL && mp->moveAbs != NULL ) {
    wprintw( term_output, "Moving %s to %f\n", mtr, fpos );
    wnoutrefresh( term_output );
    mp->moveAbs( mp, fpos );
}

```

```

    free( cmd );
}

```

5.8.2.7 void md2cmds_mvcenter.move (double cx, double cy, double ax, double ay, double az)

Move the centering and alignment tables.

Parameters

in	cx	Requested Centering Table X
in	cy	Requested Centering Table Y
in	ax	Requested Alignment Table X
in	ay	Requested Alignment Table Y
in	az	Requested Alignment Table Z

Definition at line 330 of file md2cmds.c.

```

{
    //
    // centering stage is coordinate system 2
    // alignment stage is coordinate system 3
    //

    double cx_cts, cy_cts, ax_cts, ay_cts, az_cts;

    cx_cts = md2cmds_prep_motion( cenx, cx );
    cy_cts = md2cmds_prep_motion( ceny, cy );
    ax_cts = md2cmds_prep_motion( alignx, ax );
    ay_cts = md2cmds_prep_motion( aligny, ay );
    az_cts = md2cmds_prep_motion( alignz, az );

    lspmac_SockSendline( "%2 Q100=2 Q20=%.1f Q21=%.1f B150R",
        cx_cts, cy_cts );
    md2cmds_moving_pq = lspmac_SockSendline(
        "%3 Q100=4 Q30=%.1f Q31=%.1f Q32=%.1f B160R", ax_cts, ay_cts, az_cts );
}

```

5.8.2.8 void md2cmds_mvcenter.prep ()

Sets up a centering table and alignment table move Ensures that when we issue the move command that we can detect that the move happened.

Definition at line 235 of file md2cmds.c.

```

{
    pmac_cmd_queue_t *pq;
    int flag;

    pthread_mutex_lock( &lspmac_moving_mutex );
    flag = (lspmac_moving_flags & 6) != 0;
    pthread_mutex_unlock( &lspmac_moving_mutex );

    //
    // Only wait for the all clear if it's not all clear already
    // Otherwise we may get confused
    //
    if( flag ) {
        //
        // Clears the motion flags for coordinate systems 2 and 3
        // Then sets them.
        // Each time we wait until we've read back
        // the changed values
        //
        // This guarantees that when we are waiting for motion to stop that it did,
        // in fact, start
        //

        //
        // Clear the centering and alignment stage flags
    }
}

```

```

//
pq = lspmac_SockSendline( "M5075=(M5075 | 6) ^ 6");

pthread_mutex_lock( &pmac_queue_mutex);
//
// wait for the command to be sent
//
while( pq->time_sent.tv_sec==0)
    pthread_cond_wait( &pmac_queue_cond, &pmac_queue_mutex
);
pthread_mutex_unlock( &pmac_queue_mutex);

//
// Make sure the command propagates back to the status
//
pthread_mutex_lock( &lspmac_moving_mutex);
while( (lspmac_moving_flags & 6) != 0)
    pthread_cond_wait( &lspmac_moving_cond, &
        lspmac_moving_mutex);

lslogging_log_message( "md2cmds_mvcenter_prep:
    lspmac_moving_flags = %d", lspmac_moving_flags);
pthread_mutex_unlock( &lspmac_moving_mutex);
}

//
// set a flag so the event listener doesn't send a callback too soon
//
pthread_mutex_lock( &md2cmds_moving_mutex);
md2cmds_moving_count = -1;
pthread_mutex_unlock( &md2cmds_moving_mutex);

//
// Now set the centering and alignment stage flags
//
pq = lspmac_SockSendline( "M5075=(M5075 | 6)");

pthread_mutex_lock( &pmac_queue_mutex);
//
// wait for the command to be sent
//
while( pq->time_sent.tv_sec==0)
    pthread_cond_wait( &pmac_queue_cond, &pmac_queue_mutex
);
pthread_mutex_unlock( &pmac_queue_mutex);

//
// Make sure it propagates
//
pthread_mutex_lock( &lspmac_moving_mutex);
while( (lspmac_moving_flags & 6) != 6)
    pthread_cond_wait( &lspmac_moving_cond, &
        lspmac_moving_mutex);

lslogging_log_message( "md2cmds_mvcenter_prep:
    lspmac_moving_flags = %d", lspmac_moving_flags);
pthread_mutex_unlock( &lspmac_moving_mutex);
}

```

5.8.2.9 void md2cmds_mvcenter.wait ()

Wait for the centering and alignment tables to stop moving.

Definition at line 358 of file md2cmds.c.

```

{
//
// Just wait until the motion flags are lowered
// Note this does not mean the motors are done moving,
// just that the motion program is done.
//
// Look for the "In Position" events to see if we are really done
//
// We are assuming that the "Moving" callback was received and acted on
// before the motion programs have all finished. Probably a reasonable
// expectation but not really guaranteed
//

pthread_mutex_lock( &pmac_queue_mutex);
//
// wait for the command to be sent

```

```

//
while( md2cmds_moving_pq->time_sent.tv_sec==0)
    pthread_cond_wait( &pmac_queue_cond, &pmac_queue_mutex
    );
pthread_mutex_unlock( &pmac_queue_mutex);

pthread_mutex_lock( &lspmac_moving_mutex);
while( lspmac_moving_flags & 6)
    pthread_cond_wait( &lspmac_moving_cond, &
        lspmac_moving_mutex);
pthread_mutex_unlock( &lspmac_moving_mutex);

pthread_mutex_lock( &md2cmds_moving_mutex);
while( md2cmds_moving_count > 0)
    pthread_cond_wait( &md2cmds_moving_cond, &
        md2cmds_moving_mutex);
pthread_mutex_unlock( &md2cmds_moving_mutex);
}

```

5.8.2.10 void md2cmds_phase_change (const char * ccmd)

Move md2 devices to a preconfigured state.

EMBL calls these states "phases" and this language is partially retained here

Parameters

<i>ccmd</i>	The full text of the command that sent us here
-------------	--

Definition at line 122 of file md2cmds.c.

```

{
char *cmd;
char *ignore;
char *ptr;
char *mode;

if( ccmd == NULL || *ccmd == 0)
    return;

// use a copy as strtok_r modifies the string it is parsing
//
cmd = strdup( ccmd);

ignore = strtok_r( cmd, " ", &ptr);
if( ignore == NULL) {
    lslogging_log_message( "md2cmds_phase_change: ignoring
        empty command string (how did we let things get this far?");
    free( cmd);
    return;
}

//
// ignore should point to "mode" cause that's how we got here. Ignore it
//
mode = strtok_r( NULL, " ", &ptr);
if( mode == NULL) {
    lslogging_log_message( "md2cmds_phase_change: no mode
        specified");
    free( cmd);
    return;
}

if( strcmp( mode, "manualMount") == 0) {
    lspmac_move_or_jog_preset_queue( kappa,
        "manualMount", 1);
    lspmac_move_or_jog_preset_queue( omega,
        "manualMount", 0);
    lspmac_move_or_jog_abs_queue( phi, "
        manualMount", 0);
    lspmac_move_or_jog_preset_queue( aperz,
        "Cover", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "Cover", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Cover", 1);
    md2cmds_moveAbs( "moveAbs backLight 0");
    md2cmds_moveAbs( "moveAbs backLight.intensity 0");
}

```

```

md2cmds_moveAbs( "moveAbs cryo 1");
md2cmds_moveAbs( "moveAbs fluo 0");
md2cmds_moveAbs( "moveAbs cam.zoom 1");
} else if( strcmp( mode, "robotMount") == 0) {
    lspmac_homel_queue( kappa);
    lspmac_homel_queue( omega);
    lspmac_move_or_jog_abs_queue( phi, "
        manualMount", 0);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "Cover", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Cover", 1);
    md2cmds_moveAbs( "moveAbs backLight 0");
    md2cmds_moveAbs( "moveAbs backLight.intensity 0");
    md2cmds_moveAbs( "moveAbs cryo 1");
    md2cmds_moveAbs( "moveAbs fluo 0");
    md2cmds_moveAbs( "moveAbs cam.zoom 1");
} else if( strcmp( mode, "center") == 0) {
    md2cmds_moveAbs( "moveAbs kappa 0");
    md2cmds_moveAbs( "moveAbs omega 0");
    lspmac_move_or_jog_abs_queue( phi, "
        manualMount", 0);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capy,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Cover", 1);
    md2cmds_moveAbs( "moveAbs backLight 1");
    md2cmds_moveAbs( "moveAbs cam.zoom 1");
    md2cmds_moveAbs( "moveAbs cryo 0");
    md2cmds_moveAbs( "moveAbs fluo 0");
} else if( strcmp( mode, "dataCollection") == 0) {
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capy,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Cover", 1);
    md2cmds_moveAbs( "moveAbs backLight 0");
    md2cmds_moveAbs( "moveAbs backLight.intensity 0");
    md2cmds_moveAbs( "moveAbs cryo 0");
    md2cmds_moveAbs( "moveAbs fluo 0");
} else if( strcmp( mode, "beamLocation") == 0) {
    md2cmds_moveAbs( "moveAbs kappa 0");
    md2cmds_moveAbs( "moveAbs omega 0");
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capy,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Scintillator", 1);
    md2cmds_moveAbs( "moveAbs backLight 0");
    md2cmds_moveAbs( "moveAbs cam.zoom 1");
    md2cmds_moveAbs( "moveAbs cryo 0");
    md2cmds_moveAbs( "moveAbs fluo 0");
} else if( strcmp( mode, "safe") == 0) {
    md2cmds_moveAbs( "moveAbs kappa 0");
    md2cmds_moveAbs( "moveAbs omega 0");
    lspmac_move_or_jog_preset_queue( aperz,
        "In", 1);
    lspmac_move_or_jog_preset_queue( aperz,
        "Cover", 1);
    lspmac_move_or_jog_preset_queue( capy,
        "In", 1);
    lspmac_move_or_jog_preset_queue( capz,
        "Cover", 1);
    lspmac_move_or_jog_preset_queue( scint,
        "Cover", 1);
    md2cmds_moveAbs( "moveAbs backLight 0");
    md2cmds_moveAbs( "moveAbs cam.zoom 1");

```

```

    md2cmds_moveAbs( "moveAbs cryo 0");
    md2cmds_moveAbs( "moveAbs fluo 0");
}

free( cmd);
}

```

5.8.2.11 double md2cmds_prep_motion (lspmac_motor_t * mp, double pos)

Definition at line 313 of file md2cmds.c.

```

{
    double rtn;
    double u2c;

    pthread_mutex_lock( &(mp->mutex));
    u2c = lsredis_getd( mp->u2c);

    rtn = u2c * pos;
    mp->motion_seen = 0;
    mp->not_done = 1;
    pthread_mutex_unlock( &(mp->mutex));

    return rtn;
}

```

5.8.2.12 void md2cmds_rotate ()

Spin 360 and make a video (recenter first, maybe)

< velocity (cnts/msec) for omega

Definition at line 603 of file md2cmds.c.

```

{
    int v;
    double cx, cy, ax, ay, az;
    struct timespec snooze;

    //
    // BLUMax disables scintillator here.
    //

    //
    // get the new center information
    //
    lslogging_log_message( "md2cmds_rotate: calling
        getcenter");
    lspg_getcenter_call();

    lslogging_log_message( "md2cmds_rotate: wait for
        getcenter");
    lspg_getcenter_wait();

    lslogging_log_message( "md2cmds_rotate: moving backlight
        up");
    // put up the back light
    blight_ud->moveAbs( blight_ud, 1);

    if( lspg_getcenter.no_rows_returned) {
        //
        // Always specify zoom even if no other center information is found
        //
        zoom->moveAbs( zoom, 1);    // default zoom is 1
    } else {
        lslogging_log_message( "md2cmds_rotate: getcenter
            returned dcx %f, dcy %f, dax %f, day %f, daz %f, zoom %d",
            lspg_getcenter.dcx, lspg_getcenter
                .dcy, lspg_getcenter.dax, lspg_getcenter.day
                , lspg_getcenter.daz, lspg_getcenter.zoom);

        if( lspg_getcenter.zoom_isnull == 0) {
            zoom->moveAbs( zoom, lspg_getcenter.zoom
                );
        }
    }
}

```

```

    } else {
        zoom->moveAbs( zoom, 1);
    }

    //
    // Grab the current positions and perhaps add the tad specified by
    // getcenter
    //
    cx = lspmac_getPosition( cenx);
    cy = lspmac_getPosition( ceny);
    ax = lspmac_getPosition( alignx);
    ay = lspmac_getPosition( aligny);
    az = lspmac_getPosition( alignz);
    lslogging_log_message( "md2cmds_rotate: actual
        positions cx %f, cy %f, ax %f, ay %f, az %f", cx, cy, ax, ay, az);

    if( lspg_getcenter.dcx_isnull == 0)
        cx += lspg_getcenter.dcx;

    if( lspg_getcenter.dcy_isnull == 0)
        cy += lspg_getcenter.dcy;

    if( lspg_getcenter.dax_isnull == 0)
        ax += lspg_getcenter.dax;

    if( lspg_getcenter.day_isnull == 0)
        ay += lspg_getcenter.day;

    if( lspg_getcenter.daz_isnull == 0)
        az += lspg_getcenter.daz;

    lslogging_log_message( "md2cmds_rotate: requested
        positions cx %f, cy %f, ax %f, ay %f, az %f", cx, cy, ax, ay, az);

    md2cmds_mvcenter_prep();
    lslogging_log_message( "md2cmds_rotate: moving center"
        );
    md2cmds_mvcenter_move( cx, cy, ax, ay, az);

    lslogging_log_message( "md2cmds_rotate: waiting for
        center move");
    md2cmds_mvcenter_wait();
    lslogging_log_message( "md2cmds_rotate: done waiting"
        );
}
lspg_getcenter_done();

// Omega was just homed before we mounted the sample, don't do it again here

// Report new center positions
cx = lspmac_getPosition( cenx);
cy = lspmac_getPosition( ceny);
ax = lspmac_getPosition( alignx);
ay = lspmac_getPosition( aligny);
az = lspmac_getPosition( alignz);
lspg_query_push( NULL, "SELECT px.applycenter( %.3f, %.3f,
    %.3f, %.3f, %.3f, %.3f)", cx, cy, ax, ay, az, lspmac_getPosition
    (kappa), lspmac_getPosition( phi));

lspmac_moveabs_wait( zoom);

lslogging_log_message( "md2cmds_rotate: done with
    applycenter");
lspmac_video_rotate( 4.0);
lslogging_log_message( "md2cmds_rotate: starting
    rotation");
rotating = 1;
}

```

5.8.2.13 void md2cmds_rotate_cb(char * event)

Tell the database about the time we went through omega=zero.

This should trigger the video feed server to starting making a movie.

Definition at line 701 of file md2cmds.c.

```

{
    struct tm t;
    int usecs;

```

```

    localtime_r( &(omega_zero_time.tv_sec), &t);

    lslogging_log_message( "md2cmds_rotate_cb: Here I am");

    usecs = omega_zero_time.tv_nsec / 1000;
    lspg_query_push( NULL, "SELECT px.trigcam('%d-%d-%d
        %d:%d:%d.%06d', %d, 0.0, 90.0)",
        t.tm_year+1900, t.tm_mon+1, t.tm_mday, t.tm_hour, t.tm_min,
        t.tm_sec, usecs,
        (int) (lspmac_getPosition( zoom)));
}

```

5.8.2.14 void md2cmds_run ()

Start up the thread.

Definition at line 794 of file md2cmds.c.

```

{
    pthread_create( &md2cmds_thread, NULL,
        md2cmds_worker, NULL);
    lsevents_add_listener( "omega crossed zero",
        md2cmds_rotate_cb);
    lsevents_add_listener( "omega In Position",
        md2cmds_maybe_rotate_done_cb);
    lsevents_add_listener( "align.x In Position",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "align.y In Position",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "align.z In Position",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "centering.x In Position",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "centering.y In Position",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "align.x Moving",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "align.y Moving",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "align.z Moving",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "centering.x Moving",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "centering.y Moving",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "cam.zoom In Position",
        md2cmds_set_scale_cb);
}

```

5.8.2.15 void md2cmds_set_scale_cb (char * event)

Fix up xscale and yscale when zoom changes.

Definition at line 728 of file md2cmds.c.

```

{
    int mag;

    mag = lspmac_getPosition( zoom);
    lspg_query_push( NULL, "SELECT pmac.md2_set_scales( %d)", mag)
    ;
}

```

5.8.2.16 void md2cmds_transfer ()

Transfer a sample TODO: Implement.

Definition at line 29 of file md2cmds.c.

```

{

```


5.8.2.17 void* md2cmds_worker (void * dummy)

Our worker thread.

Parameters

<i>dummy</i>	[in] Unused but required by protocol
--------------	--------------------------------------

Definition at line 746 of file md2cmds.c.

```

{
pthread_mutex_lock( &md2cmds_mutex);

while( 1) {
//
// wait for someone to give us a command (and tell us they did so)
//
while( md2cmds_cmd[0] == 0)
pthread_cond_wait( &md2cmds_cond, &md2cmds_mutex
);

if( strcmp( md2cmds_cmd, "transfer") == 0) {
md2cmds_transfer();
} else if( strcmp( md2cmds_cmd, "collect") == 0) {
md2cmds_collect();
} else if( strcmp( md2cmds_cmd, "rotate") == 0) {
md2cmds_rotate();
} else if( strcmp( md2cmds_cmd, "center") == 0) {
md2cmds_center();
} else if( strncmp( md2cmds_cmd, "moveAbs", 7) == 0) {
md2cmds_moveAbs( md2cmds_cmd);
} else if( strncmp( md2cmds_cmd, "changeMode", 10) == 0) {
md2cmds_phase_change( md2cmds_cmd);
}

md2cmds_cmd[0] = 0;
}
}

```

5.8.3 Variable Documentation**5.8.3.1 char md2cmds_cmd[MD2CMDS_CMD_LENGTH]**

our command;

Definition at line 19 of file md2cmds.c.

5.8.3.2 pthread_cond_t md2cmds_cond

condition to signal when it's time to run an md2 command

Definition at line 10 of file md2cmds.c.

5.8.3.3 pthread_cond_t md2cmds_moving_cond

coordinate call and response

Definition at line 13 of file md2cmds.c.

5.8.3.4 int md2cmds_moving_count = 0

Definition at line 17 of file md2cmds.c.

5.8.3.5 pthread_mutex_t md2cmds_moving_mutex

message passing between md2cmds and pg

Definition at line 14 of file md2cmds.c.

5.8.3.6 pmac_cmd_queue_t* md2cmds_moving_pq

pmac queue item from last command

Definition at line 15 of file md2cmds.c.

5.8.3.7 pthread_mutex_t md2cmds_mutex

mutex for the condition

Definition at line 11 of file md2cmds.c.

5.8.3.8 pthread_t md2cmds_thread [static]

Definition at line 21 of file md2cmds.c.

5.8.3.9 int rotating = 0 [static]

flag: when omega is in position after a rotate we want to re-home omega

Definition at line 23 of file md2cmds.c.

5.9 pgpmac.c File Reference

Main for the pgpmac project.

```
#include "pgpmac.h"
```

Functions

- void [stdinService](#) (struct pollfd *evt)
Handle keyboard input.
- void [pgpmac_printf](#) (char *fmt,...)
Terminal output routine ala printf.
- int [main](#) (int argc, char **argv)
Our main routine.

Variables

- WINDOW * [term_output](#)
place to print stuff out
- WINDOW * [term_input](#)
place to put the cursor
- WINDOW * [term_status](#)
shutter, lamp, air, etc status
- WINDOW * [term_status2](#)

- shutter, lamp, air, etc status*
- pthread_mutex_t [ncurses_mutex](#)
allow more than one thread access to the screen
- static struct pollfd [stdinfda](#)
Handle input from the keyboard.

5.9.1 Detailed Description

Main for the pgpmac project.

Date

2012

Author

Keith Brister

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Definition in file [pgpmac.c](#).

5.9.2 Function Documentation

5.9.2.1 int main (int argc, char ** argv)

Our main routine.

Parameters

in	<i>argc</i>	Number of arguments
in	<i>argv</i>	Vector of argument strings

Definition at line 349 of file pgpmac.c.

```

{
static nfds_t nfds;

static struct pollfd fda[3], *fdp;    // input for poll: room for postgres,
    pmac, and stdin
static int nfd = 0;                    // number of items in fda
static int pollrtn = 0;
static struct option long_options[] = {
    { "i-vars", 0, NULL, 'i' },
    { "m-vars", 0, NULL, 'm' },
    { NULL,     0, NULL, 0 }
};
int c;
int ivars, mvars;
mvars=0;
ivars=0;

int i;                                // standard loop counter

while( 1 ) {
    c=getopt_long( argc, argv, "im", long_options, NULL);
    if( c == -1)
        break;

    switch( c ) {
    case 'i':
        ivars=1;
        break;

```



```

        // go try to connect again
        //
        continue;
    }

    pollrtn = poll( fda, nfd, 10);

    for( i=0; pollrtn>0 && i<nfd; i++) {
        if( fda[i].revents) {
            pollrtn--;
            if( fda[i].fd == 0) {
                stdinService( &fda[i]);
            }
        }
    }
}
}
}

```

5.9.2.2 void pgpmac_printf (char * *fmt*, ...)

Terminal output routine ala printf.

Parameters

in	<i>fmt</i>	Printf style formatting string
----	------------	--------------------------------

Definition at line 326 of file pgpmac.c.

```

{
    va_list arg_ptr;

    pthread_mutex_lock( &ncurses_mutex);

    va_start( arg_ptr, fmt);
    vwprintw( term_output, fmt, arg_ptr);
    va_end( arg_ptr);

    wnoutrefresh( term_output);
    wnoutrefresh( term_input);
    doupdate();

    pthread_mutex_unlock( &ncurses_mutex);
}

```

5.9.2.3 void stdinService (struct pollfd * *evt*)

Handle keyboard input.

Parameters

in	<i>evt</i>	The pollfd object that caused this call
----	------------	---

Definition at line 254 of file pgpmac.c.

```

{
    static char cmds[1024];
    static char cntrlcmd[2];
    static char cmds_on = 0;
    int ch;

    for( ch=wgetch(term_input); ch != ERR; ch=wgetch(term_input)) {
        // wprintw( term_output, "%04x\n", ch);
        // wnoutrefresh( term_output);

        switch( ch) {
            case KEY_F(1):
                endwin();
        }
    }
}

```

```

        exit(0);
        break;

    case 0x0001:        // Control-A
    case 0x0002:        // Control-B
    case 0x0003:        // Control-C
    case 0x0004:        // Control-D
    case 0x0005:        // Control-E
    case 0x0006:        // Control-F
    case 0x0007:        // Control-G
    case 0x000b:        // Control-K
    case 0x000f:        // Control-O
    case 0x0010:        // Control-P
    case 0x0011:        // Control-Q
    case 0x0012:        // Control-R
    case 0x0013:        // Control-Q
    case 0x0016:        // Control-V
        cntrlcmd[0] = ch;
        cntrlcmd[1] = 0;
        lspmac_SockSendline( cntrlcmd);
        //      PmacSockSendControlCharPrint( ch);
        break;

    case KEY_BACKSPACE:
        cmds[cmds_on] = 0;
        cmds_on == 0 ? 0 : cmds_on--;
        break;

    case KEY_ENTER:
    case 0x000a:
        if( cmds_on > 0 && strlen( cmds) > 0) {
            lspmac_SockSendline( cmds);
        }
        memset( cmds, 0, sizeof(cmds));
        cmds_on = 0;
        break;

    default:
        if( cmds_on < sizeof( cmds)-1) {
            cmds[cmds_on++] = ch;
            cmds[cmds_on] = 0;
        }
        break;
    }
}

mvwprintw( term_input, 1, 1, "PMAC> %s", cmds);
wclrtoeol( term_input);
box( term_input, 0, 0);
wnoutrefresh( term_input);
doupdate();
}
}

```

5.9.3 Variable Documentation

5.9.3.1 pthread_mutex_t ncurses_mutex

allow more than one thread access to the screen

Definition at line 242 of file pgpmac.c.

5.9.3.2 struct pollfd stdinfd [static]

Handle input from the keyboard.

Definition at line 248 of file pgpmac.c.

5.9.3.3 WINDOW* term_input

place to put the cursor

Definition at line 238 of file pgpmac.c.

5.9.3.4 WINDOW* term_output

place to print stuff out

Definition at line 237 of file pgpmac.c.

5.9.3.5 WINDOW* term_status

shutter, lamp, air, etc status

Definition at line 239 of file pgpmac.c.

5.9.3.6 WINDOW* term_status2

shutter, lamp, air, etc status

Definition at line 240 of file pgpmac.c.

5.10 pgpmac.h File Reference

Headers for the entire pgpmac project.

```
#include <stdio.h>
#include <stdlib.h>
#include <unistd.h>
#include <sys/types.h>
#include <sys/socket.h>
#include <netdb.h>
#include <string.h>
#include <netinet/in.h>
#include <errno.h>
#include <poll.h>
#include <libpq-fe.h>
#include <ncurses.h>
#include <math.h>
#include <pthread.h>
#include <signal.h>
#include <sys/signalfd.h>
#include <sys/time.h>
#include <time.h>
#include <getopt.h>
#include <regex.h>
#include <hiredis/hiredis.h>
#include <hiredis/async.h>
#include <search.h>
```

Data Structures

- struct [lsredis_obj_struct](#)
Redis Object Basic object whose value is synchronized with our redis db.
- struct [tagEthernetCmd](#)
PMAC ethernet packet definition.
- struct [lspmac_cmd_queue_struct](#)
PMAC command queue item.

- struct [lspmac_motor_struct](#)
Motor information.
- struct [lspmac_bi_struct](#)
Storage for binary inputs.
- struct [lspg_getcenter_struct](#)
Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.
- struct [lspg_nextshot_struct](#)
Storage definition for nextshot query.

Macros

- #define [_GNU_SOURCE](#)
- #define [LS_DISPLAY_WINDOW_HEIGHT](#) 8
Number of status box rows.
- #define [LS_DISPLAY_WINDOW_WIDTH](#) 24
Number of status box columns.
- #define [LS_PG_QUERY_STRING_LENGTH](#) 1024
Fixed length postgresql query strings. Queries should all be function calls so this is not as weird as one might think.
- #define [LSEVENTS_EVENT_LENGTH](#) 32
Fixed length for event names: simplifies string handling.
- #define [MD2CMDS_CMD_LENGTH](#) 32

Typedefs

- typedef struct [lsredis_obj_struct](#) [lsredis_obj_t](#)
Redis Object Basic object whose value is synchronized with our redis db.
- typedef struct [tagEthernetCmd](#) [pmac_cmd_t](#)
PMAC ethernet packet definition.
- typedef struct
[lspmac_cmd_queue_struct](#) [pmac_cmd_queue_t](#)
PMAC command queue item.
- typedef struct [lspmac_motor_struct](#) [lspmac_motor_t](#)
Motor information.
- typedef struct [lspmac_bi_struct](#) [lspmac_bi_t](#)
Storage for binary inputs.
- typedef struct
[lspg_getcenter_struct](#) [lspg_getcenter_t](#)
Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.
- typedef struct [lspg_nextshot_struct](#) [lspg_nextshot_t](#)
Storage definition for nextshot query.

Functions

- double [lspmac_getPosition](#) ([lspmac_motor_t](#) *)
get the motor position (with locking)
- void [PmacSockSendline](#) (char *s)
- void [pgpmac_printf](#) (char *fmt,...)
Terminal output routine ala printf.
- char ** [lspg_array2ptrs](#) (char *)
returns a null terminated list of strings parsed from postgresql array

- void `lspg_init` ()
Initialize the lspg module.
- void `lspg_run` ()
Start 'er runnin'.
- void `lspg_seq_run_prep_all` (long long skey, double `kappa`, double `phi`, double cx, double cy, double ax, double ay, double az)
Convenience function to call seq run prep.
- void `lspg_zoom_lut_call` ()
- void `lspmac_init` (int, int)
Initialize this module.
- void `lspmac_run` ()
find a postion for a given preset name
- void `lspmac_move_or_jog_queue` (`lspmac_motor_t` *, double, int)
- void `lspmac_move_or_jog_preset_queue` (`lspmac_motor_t` *, char *, int)
move using a preset value
- void `lspmac_moveabs_queue` (`lspmac_motor_t` *, double)
Use coordinate system motion program, if available, to move motor to requested position.
- void `lspmac_jogabs_queue` (`lspmac_motor_t` *, double)
Use jog to move motor to requested position.
- `pmac_cmd_queue_t` * `lspmac_SockSendline` (char *,...)
Send a one line command.
- void `lsupdate_init` ()
- void `md2cmds_init` ()
Initialize the md2cmds module.
- void `md2cmds_run` ()
Start up the thread.
- void `lsupdate_run` ()
- void `lsevents_init` ()
Initialize this module.
- void `lsevents_run` ()
Start up the thread and get out of the way.
- void `lsevents_send_event` (char *,...)
Call the callback routines for the given event.
- void `lsevents_add_listener` (char *, void(*cb)(char *))
Add a callback routine to listen for a specific event.
- void `lsevents_remove_listener` (char *, void(*cb)(char *))
Remove a listener previously added with lsevents_add_listener.
- void `lstimer_init` ()
Initialize the timer list and pthread stuff.
- void `lstimer_run` ()
Start up our thread.
- void `lstimer_add_timer` (char *, int, unsigned long int, unsigned long int)
Create a timer.
- void `lsredis_init` (char *pub, char *re, char *head)
Initialize this module, that is, set up the connections.
- void `lsredis_run` ()
- `lsredis_obj_t` * `lsredis_get_obj` (char *,...)
- char * `lsredis_getstr` (`lsredis_obj_t` *p)
return a copy of the key's string value
- double `lsredis_getd` (`lsredis_obj_t` *p)
- long int `lsredis_getl` (`lsredis_obj_t` *p)

- `char ** lsredis_get_string_array (lsredis_obj_t *p)`
- `int lsredis_getb (lsredis_obj_t *p)`
- `int lsredis_cmpstr (lsredis_obj_t *p, char *s)`
- `int lsredis_regexec (const regex_t *preg, lsredis_obj_t *p, size_t nmatch, regmatch_t *pmatch, int eflags)`
- `int lsredis_cmpnstr (lsredis_obj_t *p, char *s, int n)`
- `int lsredis_find_preset (char *base, char *preset_name, double *dval)`

Variables

- `lspg_getcenter_t lspg_getcenter`
the getcenter object
- `lspg_nextshot_t lspg_nextshot`
the nextshot object
- `lspmac_motor_t lspmac_motors []`
All our motors.
- `lspmac_motor_t * omega`
MD2 omega axis (the air bearing)
- `lspmac_motor_t * alignx`
Alignment stage X.
- `lspmac_motor_t * aligny`
Alignment stage Y.
- `lspmac_motor_t * alignz`
Alignment stage X.
- `lspmac_motor_t * anal`
Polaroid analyzer motor.
- `lspmac_motor_t * zoom`
Optical zoom.
- `lspmac_motor_t * apery`
Aperture Y.
- `lspmac_motor_t * aperz`
Aperture Z.
- `lspmac_motor_t * capy`
Capillary Y.
- `lspmac_motor_t * capz`
Capillary Z.
- `lspmac_motor_t * scint`
Scintillator Z.
- `lspmac_motor_t * cenx`
Centering Table X.
- `lspmac_motor_t * ceny`
Centering Table Y.
- `lspmac_motor_t * kappa`
Kappa.
- `lspmac_motor_t * phi`
Phi (not data collection axis)
- `lspmac_motor_t * fshut`
Fast shutter.
- `lspmac_motor_t * flight`
Front Light DAC.
- `lspmac_motor_t * blight`
Back Light DAC.

- [lspmac_motor_t * fscint](#)
Scintillator Piezo DAC.
- [lspmac_motor_t * blight_ud](#)
Back light Up/Down actuator.
- [lspmac_motor_t * flight_oo](#)
Turn front light on/off.
- [lspmac_motor_t * blight_f](#)
Back light scale factor.
- [lspmac_motor_t * flight_f](#)
Front light scale factor.
- [lspmac_motor_t * cryo](#)
Move the cryostream towards or away from the crystal.
- [lspmac_motor_t * dryer](#)
blow air on the scintillator to dry it off
- [lspmac_motor_t * fluo](#)
Move the fluorescence detector in/out.
- [int lspmac_nmotors](#)
The number of motors we manage.
- [struct timespec omega_zero_time](#)
Time we believe that omega crossed zero.
- [WINDOW * term_output](#)
place to print stuff out
- [WINDOW * term_input](#)
place to put the cursor
- [WINDOW * term_status](#)
shutter, lamp, air, etc status
- [WINDOW * term_status2](#)
shutter, lamp, air, etc status
- [pthread_mutex_t ncurses_mutex](#)
allow more than one thread access to the screen
- [pthread_cond_t md2cmds_cond](#)
condition to signal when it's time to run an md2 command
- [pthread_mutex_t md2cmds_mutex](#)
mutex for the condition
- [pthread_cond_t md2cmds_pg_cond](#)
- [pthread_mutex_t md2cmds_pg_mutex](#)
- [pthread_mutex_t pmac_queue_mutex](#)
manage access to the pmac command queue
- [pthread_cond_t pmac_queue_cond](#)
wait for a command to be sent to PMAC before continuing
- [pthread_mutex_t lspmac_shutter_mutex](#)
Coordinates threads reading shutter status.
- [pthread_cond_t lspmac_shutter_cond](#)
Allows waiting for the shutter status to change.
- [int lspmac_shutter_state](#)
State of the shutter, used to detect changes.
- [int lspmac_shutter_has_opened](#)
Indicates that the shutter had opened, perhaps briefly even if the state did not change.
- [pthread_mutex_t lspmac_moving_mutex](#)
Coordinate moving motors between threads.
- [pthread_cond_t lspmac_moving_cond](#)

- Wait for motor(s) to finish moving condition.*
 - int [lspmac_moving_flags](#)
Flag used to implement motor moving condition.
 - pthread_mutex_t [md2_status_mutex](#)
Synchronize reading/writing status buffer.
 - char [md2cmds_cmd](#) []
our command;

5.10.1 Detailed Description

Headers for the entire pgpmac project.

Date

2012

Author

Keith Brister

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Definition in file [pgpmac.h](#).

5.10.2 Macro Definition Documentation

5.10.2.1 #define _GNU_SOURCE

Definition at line 7 of file pgpmac.h.

5.10.2.2 #define LS_DISPLAY_WINDOW_HEIGHT 8

Number of status box rows.

Definition at line 56 of file pgpmac.h.

5.10.2.3 #define LS_DISPLAY_WINDOW_WIDTH 24

Number of status box columns.

Definition at line 60 of file pgpmac.h.

5.10.2.4 #define LS_PG_QUERY_STRING_LENGTH 1024

Fixed length postgresql query strings. Queries should all be function calls so this is not as weird as one might think.

Definition at line 63 of file pgpmac.h.

5.10.2.5 #define LSEVENTS_EVENT_LENGTH 32

Fixed length for event names: simplifies string handling.

Definition at line 66 of file pgpmac.h.

5.10.2.6 `#define MD2CMDS_CMD_LENGTH 32`

Definition at line 388 of file pgpmac.h.

5.10.3 Typedef Documentation

5.10.3.1 `typedef struct lspg_getcenter_struct lspg_getcenter_t`

Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.

5.10.3.2 `typedef struct lspg_nextshot_struct lspg_nextshot_t`

Storage definition for nextshot query.

The next shot query returns all the information needed to collect the next data frame. Since SQL allows for null fields independently from blank strings a separate integer is used as a flag for this case. This adds to the program complexity but allows for some important cases. Suck it up.definition of the next image to be taken (and the one after that, too!)

5.10.3.3 `typedef struct lspmac_bi_struct lspmac_bi_t`

Storage for binary inputs.

5.10.3.4 `typedef struct lspmac_motor_struct lspmac_motor_t`

Motor information.

A catchall for motors and motor like objects. Not all members are used by all objects.

5.10.3.5 `typedef struct lsredis_obj_struct lsredis_obj_t`

Redis Object Basic object whose value is synchronized with our redis db.

5.10.3.6 `typedef struct lspmac_cmd_queue_struct pmac_cmd_queue_t`

PMAC command queue item.

Command queue items are fixed length to simplify memory management.

5.10.3.7 `typedef struct tagEthernetCmd pmac_cmd_t`

PMAC ethernet packet definition.

Taken directly from the Delta Tau documentation.

5.10.4 Function Documentation

5.10.4.1 `void lsevents_add_listener (char * event, void (*)(char *) cb)`

Add a callback routine to listen for a specific event.

Parameters

<i>event</i>	the name of the event to listen for
<i>cb</i>	the routine to call

Definition at line 78 of file lsevents.c.

```

{
lsevents_listener_t *new;
int err;
char *errbuf;
int nerrbuf;

new = calloc( 1, sizeof( lsevents_listener_t));
if( new == NULL) {
    lslogging_log_message( "lsevents_add_listener: out of
        memory");
    exit( -1);
}

err = regcomp( &new->re, event, REG_EXTENDED | REG_NOSUB);
if( err != 0) {
    nerrbuf = regerror( err, &new->re, NULL, 0);
    errbuf = calloc( nerrbuf, sizeof( char));
    if( errbuf == NULL) {
        lslogging_log_message( "lsevents_add_listener: out
            of memory (re)");
        exit( -1);
    }
    regerror( err, &new->re, errbuf, nerrbuf);
    lslogging_log_message( "lsevents_add_listener: %s",
        errbuf);
    free( errbuf);
    free( new);
    return;
}

new->raw_regexp = strdup( event);
new->cb = cb;

pthread_mutex_lock( &lsevents_listener_mutex);
new->next = lsevents_listeners_p;
lsevents_listeners_p = new;
pthread_mutex_unlock( &lsevents_listener_mutex);

lslogging_log_message( "lsevents_add_listener: added
    listener for event %s", event);
}

```

5.10.4.2 void lsevents_init ()

Initialize this module.

Definition at line 207 of file lsevents.c.

```

{
pthread_mutex_init( &lsevents_queue_mutex, NULL);
pthread_cond_init( &lsevents_queue_cond, NULL);
pthread_mutex_init( &lsevents_listener_mutex, NULL);
}

```

5.10.4.3 void lsevents_remove_listener (char * event, void (*)(char *) cb)

Remove a listener previously added with lsevents_add_listener.

Parameters

<i>event</i>	The name of the event
<i>cb</i>	The callback routine to remove

Definition at line 123 of file lsevents.c.

```

{

```

```

lsevents_listener_t *last, *current;

//
// Find the listener to remove
// and unlink it from the list
//
pthread_mutex_lock( &lsevents_listener_mutex);
last = NULL;
for( current = lsevents_listeners_p; current != NULL;
    current = current->next) {
    if( strcmp( last->raw_regexp, event) == 0 && last->cb == cb) {
        if( last == NULL) {
            lsevents_listeners_p = current->next;
        } else {
            last->next = current->next;
        }
        break;
    }
}
pthread_mutex_unlock( &lsevents_listener_mutex);

//
// Now remove it
//
if( current != NULL) {
    if( current->raw_regexp != NULL)
        free( current->raw_regexp);
    free(current);
}
}

```

5.10.4.4 void lsevents_run ()

Start up the thread and get out of the way.

Definition at line 215 of file lsevents.c.

```

{
    pthread_create( &lsevents_thread, NULL, lsevents_worker
, NULL);
}

```

5.10.4.5 void lsevents_send_event (char *fmt, ...)

Call the callback routines for the given event.

Parameters

<i>fmt</i>	a printf style formatting string
...	list of arguments specified by the format string

Definition at line 45 of file lsevents.c.

```

{
    char event[LSEVENTS_EVENT_LENGTH];
    char *sp;
    va_list arg_ptr;

    va_start( arg_ptr, fmt);
    vsnprintf( event, sizeof(event)-1, fmt, arg_ptr);
    event[sizeof(event)-1]=0;
    va_end( arg_ptr);

    pthread_mutex_lock( &lsevents_queue_mutex);

    lslogging_log_message( "lsevents_send_event: %s", event)
;

    // maybe wait for room on the queue
    while( lsevents_queue_on + 1 == lsevents_queue_off
    )
        pthread_cond_wait( &lsevents_queue_cond, &

```

```

        lsevents_queue_mutex);

    sp = lsevents_queue[(lsevents_queue_on++) %
        LSEVENTS_QUEUE_LENGTH].event;
    strncpy( sp, event, LSEVENTS_EVENT_LENGTH);
    sp[LSEVENTS_EVENT_LENGTH - 1] = 0;

    pthread_cond_signal( &lsevents_queue_cond);
    pthread_mutex_unlock( &lsevents_queue_mutex);
}

```

5.10.4.6 char** lspg_array2ptrs (char *)

returns a null terminated list of strings parsed from postgresql array

Definition at line 165 of file lspg.c.

```

{
    char **rtn, *sp, *acums;
    int i, n, inquote, havebackslash, rtni;;
    int mxsz;

    inquote      = 0;
    havebackslash = 0;

    // Despense with the null input condition before we complicate the code below
    if( a == NULL || a[0] == 0)
        return NULL;

    // Count the maximum number of strings
    // Actual number will be less if there are quoted commas
    //
    n = 1;
    for( i=0; a[i]; i++) {
        if( a[i] == ',')
            n++;
    }
    //
    // The maximum size of any string is the length of a (+1)
    //
    mxsz = strlen(a) + 1;

    // This is the accumulation string to make up the array elements
    acums = (char *)calloc( mxsz, sizeof( char));
    if( acums == NULL) {
        // TODO: print or otherwise log this condition
        // out of memory
        exit( 1);
    }

    //
    // allocate storage for the pointer array and the null terminator
    //
    rtn = (char **)calloc( n+1, sizeof( char *));
    if( rtn == NULL) {
        // TODO: print or otherwise log this condition
        // out of memory
        exit( 1);
    }
    rtni = 0;

    // Go through and create the individual strings
    sp = acums;
    *sp = 0;
    if( a[0] != '{') {
        // oh no! This isn't an array after all!
        // Zounds!
        return NULL;
    }
    inquote = 0;
    havebackslash = 0;
    for( i=1; a[i] != 0; i++) {
        switch( a[i]) {
            case '"':
                if( havebackslash) {
                    // a quoted quote. Cool
                    //
                    *(sp++) = a[i];
                    *sp = 0;
                    havebackslash = 0;
                } else {

```



```

        // Toggle the flag
        inquote = 1 - inquote;
    }
    break;

case '\\':
    if( havebackslash) {
        *(sp++) = a[i];
        *sp = 0;
        havebackslash = 0;
    } else {
        havebackslash = 1;
    }
    break;

case ',':
    if( inquote || havebackslash) {
        *(sp++) = a[i];
        *sp = 0;
        havebackslash = 0;
    } else {
        rtn[rtni++] = strdup( acums);
        sp = acums;
    }
    break;

case ')':
    if( inquote || havebackslash) {
        *(sp++) = a[i];
        *sp = 0;
        havebackslash = 0;
    } else {
        rtn[rtni++] = strdup( acums);
        rtn[rtni] = NULL;
        return( rtn);
    }
    break;

default:
    *(sp++) = a[i];
    *sp = 0;
    havebackslash = 0;
}
}
//
// Getting here means the final ')' was missing
// Probably we should throw an error or log it or something.
//
rtn[rtni++] = strdup( acums);
rtn[rtni] = NULL;
return( rtn);
}

```

5.10.4.7 void lspg_init ()

Initialize the lspg module.

Definition at line 1615 of file lspg.c.

```

{
    pthread_mutex_init( &lspg_queue_mutex, NULL);
    pthread_cond_init( &lspg_queue_cond, NULL);
    lspg_nextshot_init();
    lspg_getcenter_init();
    lspg_wait_for_detector_init();
    lspg_lock_diffractionmeter_init();
    lspg_lock_detector_init();
}

```

5.10.4.8 void lspg_run ()

Start 'er runnin'.

Definition at line 1627 of file lspg.c.

```

{
    pthread_create( &lspg_thread, NULL, lspg_worker, NULL);
}

```

5.10.4.9 `void lspg_seq_run_prep_all (long long skey, double kappa, double phi, double cx, double cy, double ax, double ay, double az)`

Convenience function to call seq run prep.

Parameters

in	<i>skey</i>	px.shots key for this image
in	<i>kappa</i>	current kappa postion
in	<i>phi</i>	current phi postition
in	<i>cx</i>	current center table x
in	<i>cy</i>	current center table y
in	<i>ax</i>	current alignment table x
in	<i>ay</i>	current alignment table y
in	<i>az</i>	current alignment table z

Definition at line 952 of file lspg.c.

```

{
    lspg_seq_run_prep_call( skey, kappa, phi, cx,
        cy, ax, ay, az);
    lspg_seq_run_prep_wait();
    lspg_seq_run_prep_done();
}
```

5.10.4.10 `void lspg_zoom_lut.call ()`

5.10.4.11 `double lspmac_getPosition (lspmac_motor_t * mp)`

get the motor position (with locking)

Parameters

<i>mp</i>	the motor object
-----------	------------------

Definition at line 1236 of file lspmac.c.

```

{
    double rtn;
    pthread_mutex_lock( &(mp->mutex));
    rtn = mp->position;
    pthread_mutex_unlock( &(mp->mutex));
    return rtn;
}
```

5.10.4.12 `void lspmac_init (int, int)`

Initialize this module.

Definition at line 2528 of file lspmac.c.

```

{
    md2_status_t *p;

    // Set our global harvest flags
    getivars = ivarsflag;
    getmvars = mvarsflag;

    // All important status mutex
    pthread_mutex_init( &md2_status_mutex, NULL);

    //
    // Get the MD2 initialization strings
```

```

//
lspmac_md2_init = lsredis_get_obj( "
    md2_pmac.init");

//
// Initialize the motor objects
//

p = &md2_status;

omega = lspmac_motor_init( &(lspmac_motors
    [ 0]), 0, 0, &p->omega_act_pos, &p->omega_status_1
    , &p->omega_status_2, "Omega #1 &1 A", "omega",
    lspmac_moveabs_queue);
alignx = lspmac_motor_init( &(lspmac_motors
    [ 1]), 0, 1, &p->alignx_act_pos, &p->alignx_status_1
    , &p->alignx_status_2, "Align X #2 &3 X", "align.x",
    lspmac_moveabs_queue);
aligny = lspmac_motor_init( &(lspmac_motors
    [ 2]), 0, 2, &p->aligny_act_pos, &p->aligny_status_1
    , &p->aligny_status_2, "Align Y #3 &3 Y", "align.y",
    lspmac_moveabs_queue);
alignz = lspmac_motor_init( &(lspmac_motors
    [ 3]), 0, 3, &p->alignz_act_pos, &p->alignz_status_1
    , &p->alignz_status_2, "Align Z #4 &3 Z", "align.z",
    lspmac_moveabs_queue);
anal = lspmac_motor_init( &(lspmac_motors
    [ 4]), 0, 4, &p->analyzer_act_pos, &p->analyzer_status_1
    , &p->analyzer_status_2, "Anal #5", "lightPolar",
    lspmac_moveabs_queue);
zoom = lspmac_motor_init( &(lspmac_motors
    [ 5]), 1, 0, &p->zoom_act_pos, &p->zoom_status_1
    , &p->zoom_status_2, "Zoom #6 &4 Z", "cam.zoom",
    lspmac_movezoom_queue);
apery = lspmac_motor_init( &(lspmac_motors
    [ 6]), 1, 1, &p->aperturey_act_pos, &p->aperturey_status_1
    , &p->aperturey_status_2, "Aper Y #7 &5 Y", "appy",
    lspmac_moveabs_queue);
aperz = lspmac_motor_init( &(lspmac_motors
    [ 7]), 1, 2, &p->aperturez_act_pos, &p->aperturez_status_1
    , &p->aperturez_status_2, "Aper Z #8 &5 Z", "appz",
    lspmac_moveabs_queue);
capy = lspmac_motor_init( &(lspmac_motors
    [ 8]), 1, 3, &p->capy_act_pos, &p->capy_status_1
    , &p->capy_status_2, "Cap Y #9 &5 U", "capy",
    lspmac_moveabs_queue);
capz = lspmac_motor_init( &(lspmac_motors
    [ 9]), 1, 4, &p->capz_act_pos, &p->capz_status_1
    , &p->capz_status_2, "Cap Z #10 &5 V", "capz",
    lspmac_moveabs_queue);
scint = lspmac_motor_init( &(lspmac_motors
    [10]), 2, 0, &p->scint_act_pos, &p->scint_status_1
    , &p->scint_status_2, "Scin Z #11 &5 W", "scint",
    lspmac_moveabs_queue);
cenx = lspmac_motor_init( &(lspmac_motors
    [11]), 2, 1, &p->centerx_act_pos, &p->centerx_status_1
    , &p->centerx_status_2, "Cen X #17 &2 X", "centering.x",
    lspmac_moveabs_queue);
ceny = lspmac_motor_init( &(lspmac_motors
    [12]), 2, 2, &p->centery_act_pos, &p->centery_status_1
    , &p->centery_status_2, "Cen Y #18 &2 Y", "centering.y",
    lspmac_moveabs_queue);
kappa = lspmac_motor_init( &(lspmac_motors
    [13]), 2, 3, &p->kappa_act_pos, &p->kappa_status_1
    , &p->kappa_status_2, "Kappa #19 &7 X", "kappa",
    lspmac_moveabs_queue);
phi = lspmac_motor_init( &(lspmac_motors[
    14]), 2, 4, &p->phi_act_pos, &p->phi_status_1
    , &p->phi_status_2, "Phi #20 &7 Y", "phi",
    lspmac_moveabs_queue);

fshut = lspmac_fshut_init( &(lspmac_motors
    [15]));
flight = lspmac_dac_init( &(lspmac_motors[1
    6]), &p->front_dac, "M1200", "frontLight.intensity",
    lspmac_movedac_queue);
blight = lspmac_dac_init( &(lspmac_motors[1
    7]), &p->back_dac, "M1201", "backLight.intensity",
    lspmac_movedac_queue);
fscint = lspmac_dac_init( &(lspmac_motors[1
    8]), &p->scint_piezo, "M1203", "scint.focus",
    lspmac_movedac_queue);

blight_ud = lspmac_bo_init( &(lspmac_motors
    [19]), "backLight", "M1101=%d", &(md2_status.acc11c_5), 0x02)
;
cryo = lspmac_bo_init( &(lspmac_motors[20

```

```

    }), "cryo",          "M1102=%d", &(md2_status.acc11c_5), 0x04);
dryer   = lspmac_bo_init( &(lspmac_motors[2
1]), "dryer",          "M1103=%d", &(md2_status.acc11c_5), 0x08);
fluo    = lspmac_bo_init( &(lspmac_motors[22
]), "fluo",           "M1008=%d", &(md2_status.acc11c_2), 0x01);
flight_oo = lspmac_soft_motor_init( &(
    lspmac_motors[23]), "frontLight",
    lspmac_moveabs_frontlight_oo_queue);
blight_f = lspmac_soft_motor_init( &(
    lspmac_motors[24]), "backLight.factor",
    lspmac_moveabs_blight_factor_queue);
flight_f = lspmac_soft_motor_init( &(
    lspmac_motors[25]), "frontLight.factor",
    lspmac_moveabs_flight_factor_queue);

cryo_switch = lspmac_bi_init( &(lspmac_bis
[0]), &(md2_status.acc11c_1), 0x04, "CryoSwitchChanged", "
CryoSwitchChanged");

//
// Initialize several commands that get called, perhaps, alot
//
rr_cmd.RequestType = VR_UPLOAD;
rr_cmd.Request     = VR_PMAC_READREADY;
rr_cmd.wValue      = 0;
rr_cmd.wIndex      = 0;
rr_cmd.wLength     = htons(2);
memset( rr_cmd.bData, 0, sizeof(rr_cmd.bData));

gb_cmd.RequestType = VR_UPLOAD;
gb_cmd.Request     = VR_PMAC_GETBUFFER;
gb_cmd.wValue      = 0;
gb_cmd.wIndex      = 0;
gb_cmd.wLength     = htons(1400);
memset( gb_cmd.bData, 0, sizeof(gb_cmd.bData));

cr_cmd.RequestType = VR_UPLOAD;
cr_cmd.Request     = VR_CTRL_RESPONSE;
cr_cmd.wValue      = 0;
cr_cmd.wIndex      = 0;
cr_cmd.wLength     = htons(1400);
memset( cr_cmd.bData, 0, sizeof(cr_cmd.bData));

//
// Initialize some mutexs and conditions
//

pthread_mutex_init( &pmac_queue_mutex, NULL);
pthread_cond_init( &pmac_queue_cond, NULL);

lspmac_shutter_state = 0; //
    assume the shutter is now closed: not a big deal if we are wrong
pthread_mutex_init( &lspmac_shutter_mutex, NULL);
pthread_cond_init( &lspmac_shutter_cond, NULL);
pmacfd.fd = -1;

pthread_mutex_init( &lspmac_moving_mutex, NULL);
pthread_cond_init( &lspmac_moving_cond, NULL);
}

```

5.10.4.13 void lspmac_jogabs_queue (lspmac_motor_t *, double)

Use jog to move motor to requested position.

Definition at line 2291 of file lspmac.c.

```

{
    lspmac_move_or_jog_abs_queue( mp,
        requested_position, 1);
}

```

5.10.4.14 void lspmac_move_or_jog_preset_queue (lspmac_motor_t *, char *, int)

move using a preset value

Definition at line 2261 of file lspmac.c.

```

    {
double pos;
int err;

if( preset == NULL || *preset == 0)
    return;

err = lsredis_find_preset( mp->name, preset, &pos);

if( err != 0)
    lspmac_move_or_jog_abs_queue( mp, pos, use_jog)
    ;
}

```

5.10.4.15 void lspmac_move_or_jog_queue (lspmac_motor_t *, double, int)

5.10.4.16 void lspmac_moveabs_queue (lspmac_motor_t *, double)

Use coordinate system motion program, if available, to move motor to requested position.

Definition at line 2281 of file lspmac.c.

```

    {
lspmac_move_or_jog_abs_queue( mp,
    requested_position, 0);
}

```

5.10.4.17 void lspmac_run ()

find a position for a given preset name

Parameters

<i>mp</i>	Motor pointer
<i>name</i>	The preset to search for
<i>err</i>	set to non-zero on error, ignored if nullStart up the lspmac thread

Definition at line 2714 of file lspmac.c.

```

    {
char **inits;
lspmac_motor_t *mp;
int i;
int active;

pthread_create( &pmac_thread, NULL, lspmac_worker,
    NULL);

lsevents_add_listener( "CryoSwitchChanged",
    lspmac_cryoSwitchChanged_cb);
lsevents_add_listener( "scint In Position",
    lspmac_scint_inPosition_cb);
lsevents_add_listener( "scintDried",
    lspmac_scint_dried_cb);
lsevents_add_listener( "backLight 1",
    lspmac_backLight_up_cb);
lsevents_add_listener( "backLight 0",
    lspmac_backLight_down_cb);
lsevents_add_listener( "cam.zoom In Position",
    lspmac_light_zoom_cb);

//
// Initialize the MD2 pmac (ie, turn on the right plc's etc)
//
for( inits = lsredis_get_string_array(lspmac_md2_init
    ); *inits != NULL; inits++) {
    lspmac_SockSendline( *inits);
    // lslogging_log_message( "lspmac_init: pmac init '%s'", *inits);
}

//

```

```

// Initialize the pmac's support for each motor
// (ie, set the various flag for when a motor is active or not)
//
for( i=0; i<lspmac_nmotors; i++) {
    mp = &(lspmac_motors[i]);
    active = lsredis_getb( mp->active);

    // if there is a problem with "active" then don't do anything
    // On the other hand, various combinations of yes/no true/false 1/0 should
    // work
    //
    switch( active) {
    case 1:
        inits = lsredis_get_string_array( mp->active_init
        );
        break;

    case 0:
        inits = lsredis_get_string_array( mp->active_init
        );
        break;

    default:
        inits = NULL;
    }

    if( inits != NULL) {
        while( *inits != NULL) {
            lspmac_SockSendline( *inits);
            // lslogging_log_message( "lspmac_init: %s init '%s'", mp->name,
            *inits);
            inits++;
        }
    }
}
}

```

5.10.4.18 `pmac_cmd_queue_t* lspmac_SockSendline(char *fmt, ...)`

Send a one line command.

Uses printf style arguments.

Parameters

<code>in</code>	<code>fmt</code>	Printf style format string
-----------------	------------------	----------------------------

Definition at line 962 of file `lspmac.c`.

```

{
    va_list arg_ptr;
    char payload[1400];

    va_start( arg_ptr, fmt);
    vsnprintf( payload, sizeof(payload)-1, fmt, arg_ptr);
    payload[ sizeof(payload)-1] = 0;
    va_end( arg_ptr);

    lslogging_log_message( payload);

    return lspmac_send_command( VR_DOWNLOAD,
        VR_PMAC_SENDLINE, 0, 0, strlen( payload), payload,
        lspmac_GetShortReplyCB, 0);
}

```

5.10.4.19 `int lsredis_cmpnstr(lsredis_obj_t *p, char *s, int n)`

Definition at line 117 of file `lsredis.c`.

```

{
    int rtn;
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);
}

```

```

    rtn = strcmp( p->value, s, n);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```

5.10.4.20 int lsredis_cmpstr (lsredis_obj_t *p, char *s)

Definition at line 106 of file lsredis.c.

```

{
    int rtn;
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = strcmp( p->value, s);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```

5.10.4.21 int lsredis_find_preset (char *base, char *preset_name, double *dval)

Definition at line 694 of file lsredis.c.

```

{
    char s[512];
    int i;
    int err;
    ENTRY htab_input, *htab_output;
    lsredis_obj_t *p;

    i = 0;
    for( i=0; i<1024; i++) {
        snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.name", lsredis_head
            , base, i);
        s[sizeof(s)-1] = 0;
        htab_input.key = s;
        htab_input.data = NULL;
        err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab)
            ;
        if( err == 0) {
            // We've run out of names to look for: done
            lslogging_log_message( "lsredis_find_preset: no
                preset for motor %s named '%s'", base, preset_name);
            *dval = 0.0;
            return 0;
        }

        // Check if we have a match
        p = htab_output->data;
        if( lsredis_cmpstr( p, preset_name)==0) {
            // got a match, now look for the position
            snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.position", lsredis_head
                , base, i);
            s[sizeof(s)-1] = 0;
            htab_input.key = s;
            htab_input.data = NULL;
            err = hsearch_r( htab_input, FIND, &htab_output, &lsredis_htab)
                ;
            if( err == 0) {
                // Name but not position? odd.
                lslogging_log_message( "lsredis_find_preset:
                    Error, motor %s preset '%s' has no position defined", base, preset_name);
                *dval = 0.0;
                return 0;
            }
            p = htab_output->data;
            *dval = lsredis_getd( p);
            return 1;
        }
    }

    // How'd we get here?
    // did someone really define that many presets? And then looked for one
    // that's not there?
    *dval = 0;
    return 0;
}

```

5.10.4.22 lsredis_obj_t* lsredis_get_obj(char *, ...)

Definition at line 407 of file lsredis.c.

```

{
    lsredis_obj_t *rtn;
    va_list arg_ptr;
    char k[512];
    char *kp;
    int nkp;

    va_start( arg_ptr, fmt);
    vsnprintf( k, sizeof(k)-1, fmt, arg_ptr);
    k[sizeof(k)-1] = 0;
    va_end( arg_ptr);

    nkp = strlen(k) + strlen( lsredis_head) + 16;           // 16
               is overkill. I know. Get over it.
    kp = calloc( nkp, sizeof( char));
    if( kp == NULL) {
        lslogging_log_message( "lsredis_get_obj: Out of memory
                                ");
        exit( -1);
    }

    snprintf( kp, nkp-1, "%s.%s", lsredis_head, k);
    kp[nkp-1] = 0;
    rtn = _lsredis_get_obj( kp);
    free( kp);
    return rtn;
}

```

5.10.4.23 char** lsredis_get_string_array(lsredis_obj_t *p)

Definition at line 236 of file lsredis.c.

```

{
    char **rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = p->avalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.10.4.24 int lsredis_getb(lsredis_obj_t *p)

Definition at line 249 of file lsredis.c.

```

{
    int rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = p->bvalue;
    pthread_mutex_unlock( &p->mutex);

    return rtn;
}

```

5.10.4.25 double lsredis_getd(lsredis_obj_t *p)

Definition at line 210 of file lsredis.c.


```

    {
double rtn;

pthread_mutex_lock( &p->mutex);
while( p->valid == 0)
    pthread_cond_wait( &p->cond, &p->mutex);

rtn = p->dvalue;
pthread_mutex_unlock( &p->mutex);

return rtn;
}

```

5.10.4.26 long int lsredis_getl(lsredis_obj_t * p)

Definition at line 223 of file lsredis.c.

```

    {
long int rtn;

pthread_mutex_lock( &p->mutex);
while( p->valid == 0)
    pthread_cond_wait( &p->cond, &p->mutex);

rtn = p->lvalue;
pthread_mutex_unlock( &p->mutex);

return rtn;
}

```

5.10.4.27 char* lsredis_getstr(lsredis_obj_t * p)

return a copy of the key's string value

Definition at line 141 of file lsredis.c.

```

    {
char *rtn;

//
// Have to use strdup since we cannot guarantee that p->value won't be freed
// while the caller is still using it
//
pthread_mutex_lock( &p->mutex);
while( p->valid == 0)
    pthread_cond_wait( &p->cond, &p->mutex);

rtn = strdup(p->value);
pthread_mutex_unlock( &p->mutex);
return rtn;
}

```

5.10.4.28 void lsredis_init(char * pub, char * re, char * head)

Initialize this module, that is, set up the connections.

Parameters

<i>pub</i>	Publish under this (unique) name
<i>re</i>	Regular expression to select keys we want to mirror
<i>head</i>	Prepend this (+ a dot) to the beginning of requested objects

Definition at line 775 of file lsredis.c.

```

    {

int err;

```

```

err = hcreate_r( 8192, &lsredis_hstab);
if( err == 0) {
    lslogging_log_message( "lsredis_init: Cannot create
        hash table. Really bad things are going to happen. hcreate_r returnd %d", err);
}

lsredis_head = strdup( head);
lsredis_publisher = strdup( pub);

pthread_mutex_init( &lsredis_objs_mutex, NULL);
pthread_mutex_init( &lsredis_ro_mutex, NULL);
pthread_mutex_init( &lsredis_wr_mutex, NULL);

subac = redisAsyncConnect("127.0.0.1", 6379);
if( subac->err) {
    lslogging_log_message( "Error: %s", subac->errstr
        );
}

subfd.fd          = subac->c.fd;
subfd.events      = 0;
subac->ev.data     = &subfd;
subac->ev.addRead  = lsredis_addRead;
subac->ev.delRead  = lsredis_delRead;
subac->ev.addWrite = lsredis_addWrite;
subac->ev.delWrite = lsredis_delWrite;
subac->ev.cleanup  = lsredis_cleanup;

roac = redisAsyncConnect("127.0.0.1", 6379);
if( roac->err) {
    lslogging_log_message( "Error: %s", roac->errstr);
}

rofd.fd          = roac->c.fd;
rofd.events      = 0;
roac->ev.data     = &rofd;
roac->ev.addRead  = lsredis_addRead;
roac->ev.delRead  = lsredis_delRead;
roac->ev.addWrite = lsredis_addWrite;
roac->ev.delWrite = lsredis_delWrite;
roac->ev.cleanup  = lsredis_cleanup;

wrac = redisAsyncConnect("10.1.0.3", 6379);
if( wrac->err) {
    lslogging_log_message( "Error: %s", wrac->errstr);
}

wrfd.fd          = wrac->c.fd;
wrfd.events      = 0;
wrac->ev.data     = &wrfd;
wrac->ev.addRead  = lsredis_addRead;
wrac->ev.delRead  = lsredis_delRead;
wrac->ev.addWrite = lsredis_addWrite;
wrac->ev.delWrite = lsredis_delWrite;
wrac->ev.cleanup  = lsredis_cleanup;

lsredis_select( re);
}

```

5.10.4.29 int lsredis_regexec (const regex_t * preg, lsredis_obj_t * p, size_t nmatch, regmatch_t * pmatch, int eflags)

Definition at line 128 of file lsredis.c.

```

{
    int rtn;

    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = regexec( preg, p->value, nmatch, pmatch, eflags);

    pthread_mutex_unlock( &p->mutex);
}

```

5.10.4.30 void lsredis_run ()

Definition at line 916 of file lsredis.c.

```

    {
        pthread_create( &lsredis_thread, NULL, lsredis_worker
            , NULL);
    }

```

5.10.4.31 void lstimer_add_timer (char * event, int shots, unsigned long int secs, unsigned long int nsecs)

Create a timer.

Parameters

<i>event</i>	Name of the event to send when the timer goes off
<i>shots</i>	Number of times to run. 0 means never, -1 means forever
<i>secs</i>	Number of seconds to wait
<i>nsecs</i>	Number of nano-seconds to run in addition to secs

Definition at line 50 of file lstimer.c.

```

    {
        int i;
        struct timespec now;

        // Time we were called. Delay is based on call time, not queued time
        //
        clock_gettime( CLOCK_REALTIME, &now);

        pthread_mutex_lock( &lstimer_mutex);

        for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
            if( lstimer_list[i].shots == 0)
                break;
        }

        if( i == LSTIMER_LIST_LENGTH) {
            pthread_mutex_unlock( &lstimer_mutex);

            lslogging_log_message( "lstimer_add_timer: out of
                timers for event: %s, shots: %d, secs: %u, nsecs: %u",
                    event, shots, secs, nsecs);

            return;
        }

        strncpy( lstimer_list[i].event, event, LSEVENTS_EVENT_LENGTH
            - 1);
        lstimer_list[i].event[LSEVENTS_EVENT_LENGTH
            - 1] = 0;
        lstimer_list[i].shots      = shots;
        lstimer_list[i].delay_secs = secs;
        lstimer_list[i].delay_nsecs = nsecs;

        lstimer_list[i].next_secs = secs + now.tv_sec + (
            now.tv_nsec + nsecs) / 1000000000;
        lstimer_list[i].next_nsecs = (now.tv_nsec + nsecs)
            % 1000000000;
        lstimer_list[i].last_secs = 0;
        lstimer_list[i].last_nsecs = 0;

        lstimer_list[i].ncalls = 0;
        lstimer_list[i].init_secs = now.tv_sec;
        lstimer_list[i].init_nsecs = now.tv_nsec;

        if( shots != 0) {
            lstimer_active_timers++;
            new_timer++;
        }

        pthread_cond_signal( &lstimer_cond);
        pthread_mutex_unlock( &lstimer_mutex);
    }

```

5.10.4.32 void lstimer_init ()

Initialize the timer list and pthread stuff.

Definition at line 262 of file lstimer.c.

```

    {
        int i;

        for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
            lstimer_list[i].shots = 0;
        }

        pthread_mutex_init( &lstimer_mutex, NULL);
        pthread_cond_init( &lstimer_cond, NULL);
    }

```

5.10.4.33 void lstimer_run ()

Start up our thread.

Definition at line 276 of file lstimer.c.

```

    {
        pthread_create( &lstimer_thread, NULL, lstimer_worker
            , NULL);
    }

```

5.10.4.34 void lsupdate_init ()

5.10.4.35 void lsupdate_run ()

5.10.4.36 void md2cmds_init ()

Initialize the md2cmds module.

Definition at line 780 of file md2cmds.c.

```

    {
        memset( md2cmds_cmd, 0, sizeof( md2cmds_cmd));

        pthread_mutex_init( &md2cmds_mutex, NULL);
        pthread_cond_init( &md2cmds_cond, NULL);

        pthread_mutex_init( &md2cmds_moving_mutex, NULL);
        pthread_cond_init( &md2cmds_moving_cond, NULL);
    }

```

5.10.4.37 void md2cmds_run ()

Start up the thread.

Definition at line 794 of file md2cmds.c.

```

    {
        pthread_create( &md2cmds_thread, NULL,
            md2cmds_worker, NULL);
        lsevents_add_listener( "omega crossed zero",
            md2cmds_rotate_cb);
        lsevents_add_listener( "omega In Position",
            md2cmds_maybe_rotate_done_cb);
        lsevents_add_listener( "align.x In Position",
            md2cmds_maybe_done_moving_cb);
        lsevents_add_listener( "align.y In Position",

```

```

    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "align.z In Position",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "centering.x In Position",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "centering.y In Position",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "align.x Moving",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "align.y Moving",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "align.z Moving",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "centering.x Moving",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "centering.y Moving",
    md2cmds_maybe_done_moving_cb);
lsevents_add_listener( "cam.zoom In Position",
    md2cmds_set_scale_cb);
}

```

5.10.4.38 void pgpmac_printf (char *fmt, ...)

Terminal output routine ala printf.

Parameters

in	fmt	Printf style formatting string
----	-----	--------------------------------

Definition at line 326 of file pgpmac.c.

```

{
    va_list arg_ptr;

    pthread_mutex_lock( &ncurses_mutex);

    va_start( arg_ptr, fmt);
    vwprintw( term_output, fmt, arg_ptr);
    va_end( arg_ptr);

    wnoutrefresh( term_output);
    wnoutrefresh( term_input);
    doupdate();

    pthread_mutex_unlock( &ncurses_mutex);
}

```

5.10.4.39 void PmacSockSendline (char *s)

5.10.5 Variable Documentation

5.10.5.1 lspmac_motor_t* alignx

Alignment stage X.

Definition at line 83 of file lspmac.c.

5.10.5.2 lspmac_motor_t* aligny

Alignment stage Y.

Definition at line 84 of file lspmac.c.

5.10.5.3 lspmac_motor_t* alignz

Alignment stage X.

Definition at line 85 of file lspmac.c.

5.10.5.4 **lspmac_motor_t* anal**

Polaroid analyzer motor.

Definition at line 86 of file lspmac.c.

5.10.5.5 **lspmac_motor_t* apery**

Aperture Y.

Definition at line 88 of file lspmac.c.

5.10.5.6 **lspmac_motor_t* aperz**

Aperture Z.

Definition at line 89 of file lspmac.c.

5.10.5.7 **lspmac_motor_t* blight**

Back Light DAC.

Definition at line 100 of file lspmac.c.

5.10.5.8 **lspmac_motor_t* blight.f**

Back light scale factor.

Definition at line 105 of file lspmac.c.

5.10.5.9 **lspmac_motor_t* blight.ud**

Back light Up/Down actuator.

Definition at line 103 of file lspmac.c.

5.10.5.10 **lspmac_motor_t* capy**

Capillary Y.

Definition at line 90 of file lspmac.c.

5.10.5.11 **lspmac_motor_t* capz**

Capillary Z.

Definition at line 91 of file lspmac.c.

5.10.5.12 **lspmac_motor_t* cenx**

Centering Table X.

Definition at line 93 of file lspmac.c.

5.10.5.13 lspmac_motor_t* ceny

Centering Table Y.

Definition at line 94 of file lspmac.c.

5.10.5.14 lspmac_motor_t* cryo

Move the cryostream towards or away from the crystal.

Definition at line 107 of file lspmac.c.

5.10.5.15 lspmac_motor_t* dryer

blow air on the scintillator to dry it off

Definition at line 108 of file lspmac.c.

5.10.5.16 lspmac_motor_t* flight

Front Light DAC.

Definition at line 99 of file lspmac.c.

5.10.5.17 lspmac_motor_t* flight_f

Front light scale factor.

Definition at line 106 of file lspmac.c.

5.10.5.18 lspmac_motor_t* flight_oo

Turn front light on/off.

Definition at line 104 of file lspmac.c.

5.10.5.19 lspmac_motor_t* fluo

Move the fluorescence detector in/out.

Definition at line 109 of file lspmac.c.

5.10.5.20 lspmac_motor_t* fscint

Scintillator Piezo DAC.

Definition at line 101 of file lspmac.c.

5.10.5.21 lspmac_motor_t* fshut

Fast shutter.

Definition at line 98 of file lspmac.c.

5.10.5.22 `lspmac_motor_t*` kappa

Kappa.

Definition at line 95 of file `lspmac.c`.

5.10.5.23 `lspg_getcenter_t` lspg_getcenter

the getcenter object

Definition at line 73 of file `lspg.c`.

5.10.5.24 `lspg_nextshot_t` lspg_nextshot

the nextshot object

Definition at line 72 of file `lspg.c`.

5.10.5.25 `lspmac_motor_t` lspmac_motors[]

All our motors.

Definition at line 80 of file `lspmac.c`.

5.10.5.26 `pthread_cond_t` lspmac_moving_cond

Wait for motor(s) to finish moving condition.

Definition at line 60 of file `lspmac.c`.

5.10.5.27 `int` lspmac_moving_flags

Flag used to implement motor moving condition.

Definition at line 61 of file `lspmac.c`.

5.10.5.28 `pthread_mutex_t` lspmac_moving_mutex

Coordinate moving motors between threads.

Definition at line 59 of file `lspmac.c`.

5.10.5.29 `int` lspmac_nmotors

The number of motors we manage.

Definition at line 81 of file `lspmac.c`.

5.10.5.30 `pthread_cond_t` lspmac_shutter_cond

Allows waiting for the shutter status to change.

Definition at line 58 of file `lspmac.c`.

5.10.5.31 int lspmac_shutter_has_opened

Indicates that the shutter had opened, perhaps briefly even if the state did not change.

Definition at line 56 of file lspmac.c.

5.10.5.32 pthread_mutex_t lspmac_shutter_mutex

Coordinates threads reading shutter status.

Definition at line 57 of file lspmac.c.

5.10.5.33 int lspmac_shutter_state

State of the shutter, used to detect changes.

Definition at line 55 of file lspmac.c.

5.10.5.34 pthread_mutex_t md2_status_mutex

Synchronize reading/writing status buffer.

Definition at line 298 of file lspmac.c.

5.10.5.35 char md2cmds_cmd[]

our command;

Definition at line 19 of file md2cmds.c.

5.10.5.36 pthread_cond_t md2cmds_cond

condition to signal when it's time to run an md2 command

Definition at line 10 of file md2cmds.c.

5.10.5.37 pthread_mutex_t md2cmds_mutex

mutex for the condition

Definition at line 11 of file md2cmds.c.

5.10.5.38 pthread_cond_t md2cmds_pg_cond**5.10.5.39 pthread_mutex_t md2cmds_pg_mutex****5.10.5.40 pthread_mutex_t ncurses_mutex**

allow more than one thread access to the screen

Definition at line 242 of file pgpmac.c.

5.10.5.41 lspmac_motor_t* omega

MD2 omega axis (the air bearing)

Definition at line 82 of file lspmac.c.

5.10.5.42 `struct timespec omega_zero_time`

Time we believe that omega crossed zero.

Definition at line 65 of file `lspmac.c`.

5.10.5.43 `lspmac_motor_t* phi`

Phi (not data collection axis)

Definition at line 96 of file `lspmac.c`.

5.10.5.44 `pthread_cond_t pmac_queue_cond`

wait for a command to be sent to PMAC before continuing

Definition at line 71 of file `lspmac.c`.

5.10.5.45 `pthread_mutex_t pmac_queue_mutex`

manage access to the pmac command queue

Definition at line 70 of file `lspmac.c`.

5.10.5.46 `lspmac_motor_t* scint`

Scintillator Z.

Definition at line 92 of file `lspmac.c`.

5.10.5.47 `WINDOW* term_input`

place to put the cursor

Definition at line 238 of file `pgpmac.c`.

5.10.5.48 `WINDOW* term_output`

place to print stuff out

Definition at line 237 of file `pgpmac.c`.

5.10.5.49 `WINDOW* term_status`

shutter, lamp, air, etc status

Definition at line 239 of file `pgpmac.c`.

5.10.5.50 `WINDOW* term_status2`

shutter, lamp, air, etc status

Definition at line 240 of file `pgpmac.c`.

5.10.5.51 `lspmac_motor_t*` zoom

Optical zoom.

Definition at line 87 of file `lspmac.c`.

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