

LS-CAT PGPMAC

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Contents

1	The LS-CAT pgpmac Project	1
2	Namespace Index	5
2.1	Namespace List	5
3	Data Structure Index	7
3.1	Data Structures	7
4	File Index	9
4.1	File List	9
5	Namespace Documentation	11
5.1	iniParser Namespace Reference	11
5.1.1	Variable Documentation	11
5.1.1.1	ip	11
5.2	mk_pgpmac_redis Namespace Reference	11
5.2.1	Function Documentation	12
5.2.1.1	active_simulation	12
5.2.1.2	asis	12
5.2.2	Variable Documentation	12
5.2.2.1	b	12
5.2.2.2	bi_list	12
5.2.2.3	f	12
5.2.2.4	fnc	12
5.2.2.5	hard_ini	13
5.2.2.6	hard_ini_fields	13
5.2.2.7	head	13
5.2.2.8	hi	13
5.2.2.9	i	13
5.2.2.10	motor_dict	13
5.2.2.11	motor_field_lists	13
5.2.2.12	motor_presets	13
5.2.2.13	p	13

5.2.2.14	pi	13
5.2.2.15	ppos	14
5.2.2.16	pref_ini	14
5.2.2.17	v	14
5.2.2.18	x	14
5.2.2.19	xlate	14
5.2.2.20	y	14
5.2.2.21	zoom_settings	14
6	Data Structure Documentation	15
6.1	iniParser.iniParser Class Reference	15
6.1.1	Detailed Description	15
6.1.2	Constructor & Destructor Documentation	16
6.1.2.1	__init__	16
6.1.3	Member Function Documentation	16
6.1.3.1	get	16
6.1.3.2	has_option	16
6.1.3.3	has_section	16
6.1.3.4	options	16
6.1.3.5	read	17
6.1.3.6	sections	17
6.1.4	Field Documentation	17
6.1.4.1	f	17
6.1.4.2	sd	17
6.2	Isevents_callbacks_struct Struct Reference	17
6.2.1	Detailed Description	18
6.2.2	Field Documentation	18
6.2.2.1	cb	18
6.2.2.2	next	18
6.3	Isevents_event_names_struct Struct Reference	18
6.3.1	Detailed Description	18
6.3.2	Field Documentation	18
6.3.2.1	cbl	18
6.3.2.2	event	18
6.3.2.3	next	19
6.4	Isevents_listener_struct Struct Reference	19
6.4.1	Detailed Description	19
6.4.2	Field Documentation	19
6.4.2.1	cb	19
6.4.2.2	next	19

6.4.2.3	raw_regexp	19
6.4.2.4	re	20
6.5	Isevents_queue_struct Struct Reference	20
6.5.1	Detailed Description	20
6.5.2	Field Documentation	20
6.5.2.1	evp	20
6.6	Islogging_queue_struct Struct Reference	20
6.6.1	Detailed Description	21
6.6.2	Field Documentation	21
6.6.2.1	lmsg	21
6.6.2.2	ltime	21
6.7	Ispg_demandairrights_struct Struct Reference	21
6.7.1	Detailed Description	21
6.7.2	Field Documentation	21
6.7.2.1	cond	21
6.7.2.2	mutex	21
6.7.2.3	new_value_ready	21
6.8	Ispg_getcenter_struct Struct Reference	22
6.8.1	Detailed Description	22
6.8.2	Field Documentation	22
6.8.2.1	cond	22
6.8.2.2	dax	23
6.8.2.3	dax_isnull	23
6.8.2.4	day	23
6.8.2.5	day_isnull	23
6.8.2.6	daz	23
6.8.2.7	daz_isnull	23
6.8.2.8	dcx	23
6.8.2.9	dcx_isnull	23
6.8.2.10	dcy	23
6.8.2.11	dcy_isnull	23
6.8.2.12	mutex	24
6.8.2.13	new_value_ready	24
6.8.2.14	no_rows_returned	24
6.8.2.15	zoom	24
6.8.2.16	zoom_isnull	24
6.9	Ispg_getcurrentsampleid_struct Struct Reference	24
6.9.1	Detailed Description	25
6.9.2	Field Documentation	25
6.9.2.1	cond	25

6.9.2.2	getcurrentsampleid	25
6.9.2.3	getcurrentsampleid_isnull	25
6.9.2.4	mutex	25
6.9.2.5	new_value_ready	25
6.9.2.6	no_rows_returned	25
6.10	lspg_lock_detector_struct Struct Reference	25
6.10.1	Detailed Description	26
6.10.2	Field Documentation	26
6.10.2.1	cond	26
6.10.2.2	mutex	26
6.10.2.3	new_value_ready	26
6.11	lspg_lock_diffractionmeter_struct Struct Reference	26
6.11.1	Detailed Description	26
6.11.2	Field Documentation	26
6.11.2.1	cond	26
6.11.2.2	mutex	26
6.11.2.3	new_value_ready	27
6.12	lspg_nextsample_struct Struct Reference	27
6.12.1	Detailed Description	27
6.12.2	Field Documentation	27
6.12.2.1	cond	27
6.12.2.2	mutex	27
6.12.2.3	new_value_ready	27
6.12.2.4	nextsample	28
6.12.2.5	nextsample_isnull	28
6.12.2.6	no_rows_returned	28
6.13	lspg_nextshot_struct Struct Reference	28
6.13.1	Detailed Description	31
6.13.2	Field Documentation	31
6.13.2.1	active	31
6.13.2.2	active2	31
6.13.2.3	active2_isnull	31
6.13.2.4	active_isnull	31
6.13.2.5	ax	31
6.13.2.6	ax2	31
6.13.2.7	ax2_isnull	31
6.13.2.8	ax_isnull	31
6.13.2.9	ay	32
6.13.2.10	ay2	32
6.13.2.11	ay2_isnull	32

6.13.2.12 ay_isnull	32
6.13.2.13 az	32
6.13.2.14 az2	32
6.13.2.15 az2_isnull	32
6.13.2.16 az_isnull	32
6.13.2.17 cond	32
6.13.2.18 cx	32
6.13.2.19 cx2	33
6.13.2.20 cx2_isnull	33
6.13.2.21 cx_isnull	33
6.13.2.22 cy	33
6.13.2.23 cy2	33
6.13.2.24 cy2_isnull	33
6.13.2.25 cy_isnull	33
6.13.2.26 dsdir	33
6.13.2.27 dsdir_isnull	33
6.13.2.28 dsdist	33
6.13.2.29 dsdist2	34
6.13.2.30 dsdist2_isnull	34
6.13.2.31 dsdist_isnull	34
6.13.2.32 dsexp	34
6.13.2.33 dsexp2	34
6.13.2.34 dsexp2_isnull	34
6.13.2.35 dsexp_isnull	34
6.13.2.36 dshpid	34
6.13.2.37 dshpid_isnull	34
6.13.2.38 dskappa	34
6.13.2.39 dskappa2	35
6.13.2.40 dskappa2_isnull	35
6.13.2.41 dskappa_isnull	35
6.13.2.42 dsnrg	35
6.13.2.43 dsnrg2	35
6.13.2.44 dsnrg2_isnull	35
6.13.2.45 dsnrg_isnull	35
6.13.2.46 dsomega	35
6.13.2.47 dsomega2	35
6.13.2.48 dsomega2_isnull	35
6.13.2.49 dsomega_isnull	35
6.13.2.50 dsoscaxis	36
6.13.2.51 dsoscaxis2	36

6.13.2.52 dsoscaxis2_isnull	36
6.13.2.53 dsoscaxis_isnull	36
6.13.2.54 dsowidth	36
6.13.2.55 dsowidth2	36
6.13.2.56 dsowidth2_isnull	36
6.13.2.57 dsowidth_isnull	36
6.13.2.58 dsphi	36
6.13.2.59 dsphi2	36
6.13.2.60 dsphi2_isnull	37
6.13.2.61 dsphi_isnull	37
6.13.2.62 dspid	37
6.13.2.63 dspid_isnull	37
6.13.2.64 mutex	37
6.13.2.65 new_value_ready	37
6.13.2.66 no_rows_returned	37
6.13.2.67 sfm	37
6.13.2.68 sfm_isnull	37
6.13.2.69 sindex	37
6.13.2.70 sindex2	38
6.13.2.71 sindex2_isnull	38
6.13.2.72 sindex_isnull	38
6.13.2.73 skey	38
6.13.2.74 skey_isnull	38
6.13.2.75 sstart	38
6.13.2.76 sstart2	38
6.13.2.77 sstart2_isnull	38
6.13.2.78 sstart_isnull	38
6.13.2.79 stype	38
6.13.2.80 stype2	39
6.13.2.81 stype2_isnull	39
6.13.2.82 stype_isnull	39
6.14 lpg_seq_run_prep_struct Struct Reference	39
6.14.1 Detailed Description	39
6.14.2 Field Documentation	39
6.14.2.1 cond	39
6.14.2.2 mutex	39
6.14.2.3 new_value_ready	39
6.15 lpg_starttransfer_struct Struct Reference	40
6.15.1 Detailed Description	40
6.15.2 Field Documentation	40

6.15.2.1	cond	40
6.15.2.2	mutex	40
6.15.2.3	new_value_ready	40
6.15.2.4	no_rows_returned	40
6.15.2.5	starttransfer	41
6.16	lspg_wait_for_detector_struct Struct Reference	41
6.16.1	Detailed Description	41
6.16.2	Field Documentation	41
6.16.2.1	cond	41
6.16.2.2	mutex	41
6.16.2.3	new_value_ready	41
6.17	lspg_waitcryo_struct Struct Reference	41
6.17.1	Detailed Description	42
6.17.2	Field Documentation	42
6.17.2.1	cond	42
6.17.2.2	mutex	42
6.17.2.3	new_value_ready	42
6.18	lspgQueryQueueStruct Struct Reference	42
6.18.1	Detailed Description	43
6.18.2	Field Documentation	43
6.18.2.1	onResponse	43
6.18.2.2	qs	43
6.19	lspmac_ascii_buffers_struct Struct Reference	43
6.19.1	Detailed Description	43
6.19.2	Field Documentation	43
6.19.2.1	command_buf	43
6.19.2.2	command_buf_cc	43
6.19.2.3	command_str	44
6.19.2.4	response_buf	44
6.19.2.5	response_n	44
6.19.2.6	response_str	44
6.20	lspmac_bi_struct Struct Reference	44
6.20.1	Detailed Description	44
6.20.2	Field Documentation	45
6.20.2.1	changeEventOff	45
6.20.2.2	changeEventOn	45
6.20.2.3	first_time	45
6.20.2.4	mask	45
6.20.2.5	mutex	45
6.20.2.6	position	45

6.20.2.7	previous	45
6.20.2.8	ptr	45
6.21	Ispmac_cmd_queue_struct Struct Reference	46
6.21.1	Detailed Description	46
6.21.2	Field Documentation	46
6.21.2.1	event	46
6.21.2.2	no_reply	46
6.21.2.3	onResponse	46
6.21.2.4	pcmd	46
6.21.2.5	time_sent	47
6.22	Ispmac_combined_move_struct Struct Reference	47
6.22.1	Detailed Description	47
6.22.2	Field Documentation	47
6.22.2.1	axis	47
6.22.2.2	coord_num	47
6.22.2.3	Delta	47
6.22.2.4	moveme	47
6.23	Ispmac_dpascii_queue_struct Struct Reference	47
6.23.1	Detailed Description	48
6.23.2	Field Documentation	48
6.23.2.1	event	48
6.23.2.2	pl	48
6.24	Ispmac_motor_struct Struct Reference	48
6.24.1	Detailed Description	50
6.24.2	Field Documentation	50
6.24.2.1	active	50
6.24.2.2	active_init	50
6.24.2.3	actual_pos_cnts	51
6.24.2.4	actual_pos_cnts_p	51
6.24.2.5	axis	51
6.24.2.6	command_sent	51
6.24.2.7	cond	51
6.24.2.8	coord_num	51
6.24.2.9	dac_mvar	51
6.24.2.10	home	51
6.24.2.11	homing	51
6.24.2.12	in_position_band	52
6.24.2.13	inactive_init	52
6.24.2.14	jogAbs	52
6.24.2.15	lut	52

6.24.2.16 magic	52
6.24.2.17 max_accel	52
6.24.2.18 max_pos	52
6.24.2.19 max_speed	52
6.24.2.20 min_pos	52
6.24.2.21 motion_seen	53
6.24.2.22 motor_num	53
6.24.2.23 moveAbs	53
6.24.2.24 mutex	53
6.24.2.25 name	53
6.24.2.26 neg_limit_hit	53
6.24.2.27 neutral_pos	53
6.24.2.28 nlut	53
6.24.2.29 not_done	53
6.24.2.30 pos_limit_hit	54
6.24.2.31 position	54
6.24.2.32 pq	54
6.24.2.33 precision	54
6.24.2.34 printf_fmt	54
6.24.2.35 read	54
6.24.2.36 read_mask	54
6.24.2.37 read_ptr	54
6.24.2.38 redis_fmt	54
6.24.2.39 redis_position	55
6.24.2.40 reported_pg_position	55
6.24.2.41 reported_position	55
6.24.2.42 requested_pos_cnts	55
6.24.2.43 requested_position	55
6.24.2.44 status1	55
6.24.2.45 status1_p	55
6.24.2.46 status2	55
6.24.2.47 status2_p	55
6.24.2.48 status_str	56
6.24.2.49 u2c	56
6.24.2.50 unit	56
6.24.2.51 update_resolution	56
6.24.2.52 win	56
6.24.2.53 write_fmt	56
6.25 Isredis_obj_struct Struct Reference	56
6.25.1 Detailed Description	57

6.25.2	Field Documentation	57
6.25.2.1	avalue	57
6.25.2.2	bvalue	57
6.25.2.3	cond	57
6.25.2.4	cvalue	57
6.25.2.5	dvalue	58
6.25.2.6	events_name	58
6.25.2.7	hits	58
6.25.2.8	key	58
6.25.2.9	lvalue	58
6.25.2.10	mutex	58
6.25.2.11	next	58
6.25.2.12	valid	58
6.25.2.13	value	58
6.25.2.14	value_length	59
6.25.2.15	wait_for_me	59
6.26	Isredis_preset_list_struct Struct Reference	59
6.26.1	Detailed Description	59
6.26.2	Field Documentation	59
6.26.2.1	index	59
6.26.2.2	key	59
6.26.2.3	name	59
6.26.2.4	next	59
6.26.2.5	position	60
6.27	Istimer_list_struct Struct Reference	60
6.27.1	Detailed Description	60
6.27.2	Field Documentation	60
6.27.2.1	delay_nsecs	60
6.27.2.2	delay_secs	61
6.27.2.3	event	61
6.27.2.4	init_nsecs	61
6.27.2.5	init_secs	61
6.27.2.6	last_nsecs	61
6.27.2.7	last_secs	61
6.27.2.8	ncalls	61
6.27.2.9	next_nsecs	61
6.27.2.10	next_secs	61
6.27.2.11	shots	62
6.28	md2cmds_cmd_kv_struct Struct Reference	62
6.28.1	Detailed Description	62

6.28.2	Field Documentation	62
6.28.2.1	k	62
6.28.2.2	v	62
6.29	md2StatusStruct Struct Reference	62
6.29.1	Detailed Description	64
6.29.2	Field Documentation	64
6.29.2.1	acc11c_1	64
6.29.2.2	acc11c_2	64
6.29.2.3	acc11c_3	64
6.29.2.4	acc11c_5	64
6.29.2.5	acc11c_6	64
6.29.2.6	alignx_act_pos	64
6.29.2.7	alignx_status_1	64
6.29.2.8	alignx_status_2	64
6.29.2.9	aligny_act_pos	64
6.29.2.10	aligny_status_1	65
6.29.2.11	aligny_status_2	65
6.29.2.12	alignz_act_pos	65
6.29.2.13	alignz_status_1	65
6.29.2.14	alignz_status_2	65
6.29.2.15	analyzer_act_pos	65
6.29.2.16	analyzer_status_1	65
6.29.2.17	analyzer_status_2	65
6.29.2.18	aperturey_act_pos	65
6.29.2.19	aperturey_status_1	65
6.29.2.20	aperturey_status_2	65
6.29.2.21	aperturez_act_pos	65
6.29.2.22	aperturez_status_1	66
6.29.2.23	aperturez_status_2	66
6.29.2.24	back_dac	66
6.29.2.25	copy_act_pos	66
6.29.2.26	copy_status_1	66
6.29.2.27	copy_status_2	66
6.29.2.28	capz_act_pos	66
6.29.2.29	capz_status_1	66
6.29.2.30	capz_status_2	66
6.29.2.31	centerx_act_pos	66
6.29.2.32	centerx_status_1	66
6.29.2.33	centerx_status_2	66
6.29.2.34	centery_act_pos	67

6.29.2.35 centery_status_1	67
6.29.2.36 centery_status_2	67
6.29.2.37 dummy1	67
6.29.2.38 dummy2	67
6.29.2.39 dummy3	67
6.29.2.40 dummy4	67
6.29.2.41 dummy5	67
6.29.2.42 dummy6	67
6.29.2.43 dummy7	67
6.29.2.44 dummy8	67
6.29.2.45 dummy9	67
6.29.2.46 dummyA	68
6.29.2.47 dummyB	68
6.29.2.48 front_dac	68
6.29.2.49 fs_has_opened	68
6.29.2.50 fs_has_opened_globally	68
6.29.2.51 fs_is_open	68
6.29.2.52 kappa_act_pos	68
6.29.2.53 kappa_status_1	68
6.29.2.54 kappa_status_2	68
6.29.2.55 moving_flags	68
6.29.2.56 number_passes	68
6.29.2.57 omega_act_pos	68
6.29.2.58 omega_status_1	69
6.29.2.59 omega_status_2	69
6.29.2.60 phi_act_pos	69
6.29.2.61 phi_status_1	69
6.29.2.62 phi_status_2	69
6.29.2.63 phiscan	69
6.29.2.64 scint_act_pos	69
6.29.2.65 scint_piezo	69
6.29.2.66 scint_status_1	69
6.29.2.67 scint_status_2	69
6.29.2.68 zoom_act_pos	69
6.29.2.69 zoom_status_1	69
6.29.2.70 zoom_status_2	70
6.30 tagEthernetCmd Struct Reference	70
6.30.1 Detailed Description	70
6.30.2 Field Documentation	70
6.30.2.1 bData	70

6.30.2.2	Request	70
6.30.2.3	RequestType	71
6.30.2.4	wIndex	71
6.30.2.5	wLength	71
6.30.2.6	wValue	71
7	File Documentation	73
7.1	iniParser.py File Reference	73
7.2	lsevents.c File Reference	73
7.2.1	Detailed Description	75
7.2.2	Macro Definition Documentation	75
7.2.2.1	LSEVENTS_QUEUE_LENGTH	75
7.2.3	Typedef Documentation	75
7.2.3.1	lsevents_callbacks_t	75
7.2.3.2	lsevents_event_names_t	75
7.2.3.3	lsevents_listener_t	75
7.2.3.4	lsevents_queue_t	75
7.2.4	Function Documentation	76
7.2.4.1	lsevents_add_listener	76
7.2.4.2	lsevents_init	76
7.2.4.3	lsevents_preregister_event	77
7.2.4.4	lsevents_register_event	77
7.2.4.5	lsevents_remove_listener	78
7.2.4.6	lsevents_run	79
7.2.4.7	lsevents_send_event	79
7.2.4.8	lsevents_worker	80
7.2.5	Variable Documentation	81
7.2.5.1	lsevents_event_name_ht	81
7.2.5.2	lsevents_event_names	81
7.2.5.3	lsevents_listener_mutex	81
7.2.5.4	lsevents_listeners_p	81
7.2.5.5	lsevents_max_events	81
7.2.5.6	lsevents_n_events	81
7.2.5.7	lsevents_queue	81
7.2.5.8	lsevents_queue_cond	81
7.2.5.9	lsevents_queue_mutex	81
7.2.5.10	lsevents_queue_off	82
7.2.5.11	lsevents_queue_on	82
7.2.5.12	lsevents_thread	82
7.3	lslogging.c File Reference	82

7.3.1	Detailed Description	83
7.3.2	Macro Definition Documentation	83
7.3.2.1	LSLOGGING_FILE_NAME	83
7.3.2.2	LSLOGGING_MSG_LENGTH	84
7.3.2.3	LSLOGGING_QUEUE_LENGTH	84
7.3.3	Typedef Documentation	84
7.3.3.1	lslogging_queue_t	84
7.3.4	Function Documentation	84
7.3.4.1	lslogging_event_cb	84
7.3.4.2	lslogging_init	84
7.3.4.3	lslogging_log_message	84
7.3.4.4	lslogging_run	85
7.3.4.5	lslogging_worker	85
7.3.5	Variable Documentation	86
7.3.5.1	lslogging_cond	86
7.3.5.2	lslogging_file	86
7.3.5.3	lslogging_mutex	86
7.3.5.4	lslogging_off	86
7.3.5.5	lslogging_on	86
7.3.5.6	lslogging_queue	86
7.3.5.7	lslogging_thread	86
7.4	lspg.c File Reference	86
7.4.1	Detailed Description	92
7.4.2	Macro Definition Documentation	92
7.4.2.1	LS_PG_QUERY_QUEUE_LENGTH	92
7.4.2.2	LS_PG_STATE_IDLE	92
7.4.2.3	LS_PG_STATE_INIT	92
7.4.2.4	LS_PG_STATE_INIT_POLL	92
7.4.2.5	LS_PG_STATE_RECV	92
7.4.2.6	LS_PG_STATE_RESET	92
7.4.2.7	LS_PG_STATE_RESET_POLL	93
7.4.2.8	LS_PG_STATE_SEND	93
7.4.2.9	LS_PG_STATE_SEND_FLUSH	93
7.4.3	Typedef Documentation	93
7.4.3.1	lspg_lock_detector_t	93
7.4.3.2	lspg_lock_diffractionmeter_t	93
7.4.3.3	lspg_seq_run_prep_t	93
7.4.3.4	lspg_wait_for_detector_t	93
7.4.4	Function Documentation	93
7.4.4.1	lspg_allkvs_cb	93

7.4.4.2	lspg_array2ptrs	94
7.4.4.3	lspg_check_preset_in_position_cb	95
7.4.4.4	lspg_cmd_cb	96
7.4.4.5	lspg_demandairrights_all	96
7.4.4.6	lspg_demandairrights_call	96
7.4.4.7	lspg_demandairrights_cb	97
7.4.4.8	lspg_demandairrights_init	97
7.4.4.9	lspg_demandairrights_wait	97
7.4.4.10	lspg_flush	97
7.4.4.11	lspg_getcenter_all	98
7.4.4.12	lspg_getcenter_call	98
7.4.4.13	lspg_getcenter_cb	98
7.4.4.14	lspg_getcenter_done	99
7.4.4.15	lspg_getcenter_init	99
7.4.4.16	lspg_getcenter_wait	99
7.4.4.17	lspg_getcurrentsampleid_call	100
7.4.4.18	lspg_getcurrentsampleid_cb	100
7.4.4.19	lspg_getcurrentsampleid_init	100
7.4.4.20	lspg_getcurrentsampleid_read	101
7.4.4.21	lspg_getcurrentsampleid_wait_for_id	101
7.4.4.22	lspg_init	101
7.4.4.23	lspg_lock_detector_all	101
7.4.4.24	lspg_lock_detector_call	102
7.4.4.25	lspg_lock_detector_cb	102
7.4.4.26	lspg_lock_detector_done	102
7.4.4.27	lspg_lock_detector_init	102
7.4.4.28	lspg_lock_detector_wait	103
7.4.4.29	lspg_lock_diffractionmeter_all	103
7.4.4.30	lspg_lock_diffractionmeter_call	103
7.4.4.31	lspg_lock_diffractionmeter_cb	103
7.4.4.32	lspg_lock_diffractionmeter_done	104
7.4.4.33	lspg_lock_diffractionmeter_init	104
7.4.4.34	lspg_lock_diffractionmeter_wait	104
7.4.4.35	lspg_next_state	104
7.4.4.36	lspg_nextaction_cb	105
7.4.4.37	lspg_nextsample_all	105
7.4.4.38	lspg_nextsample_call	106
7.4.4.39	lspg_nextsample_cb	106
7.4.4.40	lspg_nextsample_done	107
7.4.4.41	lspg_nextsample_init	107

7.4.4.42	lspg_nextsample_wait	107
7.4.4.43	lspg_nextshot_call	107
7.4.4.44	lspg_nextshot_cb	108
7.4.4.45	lspg_nextshot_done	111
7.4.4.46	lspg_nextshot_init	111
7.4.4.47	lspg_nextshot_wait	112
7.4.4.48	lspg_notice_processor	112
7.4.4.49	lspg_pg_connect	112
7.4.4.50	lspg_pg_service	113
7.4.4.51	lspg_preset_changed_cb	115
7.4.4.52	lspg_query_next	115
7.4.4.53	lspg_query_push	115
7.4.4.54	lspg_query_reply_next	116
7.4.4.55	lspg_query_reply_peek	116
7.4.4.56	lspg_receive	117
7.4.4.57	lspg_run	118
7.4.4.58	lspg_sample_detector_cb	118
7.4.4.59	lspg_send_next_query	118
7.4.4.60	lspg_seq_run_prep_all	119
7.4.4.61	lspg_seq_run_prep_call	119
7.4.4.62	lspg_seq_run_prep_cb	120
7.4.4.63	lspg_seq_run_prep_done	120
7.4.4.64	lspg_seq_run_prep_init	120
7.4.4.65	lspg_seq_run_prep_wait	120
7.4.4.66	lspg_set_scale_cb	121
7.4.4.67	lspg_sig_service	121
7.4.4.68	lspg_starttransfer_all	121
7.4.4.69	lspg_starttransfer_call	122
7.4.4.70	lspg_starttransfer_cb	122
7.4.4.71	lspg_starttransfer_done	122
7.4.4.72	lspg_starttransfer_init	122
7.4.4.73	lspg_starttransfer_wait	123
7.4.4.74	lspg_unset_current_preset_moving_cb	123
7.4.4.75	lspg_update_kvs_cb	123
7.4.4.76	lspg_wait_for_detector_all	124
7.4.4.77	lspg_wait_for_detector_call	124
7.4.4.78	lspg_wait_for_detector_cb	124
7.4.4.79	lspg_wait_for_detector_done	125
7.4.4.80	lspg_wait_for_detector_init	125
7.4.4.81	lspg_wait_for_detector_wait	125

7.4.4.82	lspg_waitcryo_all	125
7.4.4.83	lspg_waitcryo_cb	126
7.4.4.84	lspg_waitcryo_init	126
7.4.4.85	lspg_worker	126
7.4.5	Variable Documentation	127
7.4.5.1	ls_pg_state	127
7.4.5.2	lspg_connectPoll_response	127
7.4.5.3	lspg_demandairrights	127
7.4.5.4	lspg_getcenter	127
7.4.5.5	lspg_getcurrentsampleid	127
7.4.5.6	lspg_lock_detector	128
7.4.5.7	lspg_lock_diffractionmeter	128
7.4.5.8	lspg_nextsample	128
7.4.5.9	lspg_nextshot	128
7.4.5.10	lspg_query_queue	128
7.4.5.11	lspg_query_queue_off	128
7.4.5.12	lspg_query_queue_on	128
7.4.5.13	lspg_query_queue_reply	128
7.4.5.14	lspg_queue_cond	128
7.4.5.15	lspg_queue_mutex	129
7.4.5.16	lspg_resetPoll_response	129
7.4.5.17	lspg_seq_run_prep	129
7.4.5.18	lspg_starttransfer	129
7.4.5.19	lspg_thread	129
7.4.5.20	lspg_wait_for_detector	129
7.4.5.21	lspg_waitcryo	129
7.4.5.22	lspgfd	129
7.4.5.23	now	129
7.4.5.24	q	130
7.5	lspmac.c File Reference	130
7.5.1	Detailed Description	138
7.5.2	Macro Definition Documentation	139
7.5.2.1	LS_PMAC_STATE_CR	139
7.5.2.2	LS_PMAC_STATE_DETACHED	139
7.5.2.3	LS_PMAC_STATE_GB	139
7.5.2.4	LS_PMAC_STATE_GMR	139
7.5.2.5	LS_PMAC_STATE_IDLE	139
7.5.2.6	LS_PMAC_STATE_RESET	140
7.5.2.7	LS_PMAC_STATE_RR	140
7.5.2.8	LS_PMAC_STATE_SC	140

7.5.2.9	LS_PMAC_STATE_WACK	140
7.5.2.10	LS_PMAC_STATE_WACK_CC	140
7.5.2.11	LS_PMAC_STATE_WACK_NFR	140
7.5.2.12	LS_PMAC_STATE_WACK_RR	140
7.5.2.13	LS_PMAC_STATE_WCR	140
7.5.2.14	LS_PMAC_STATE_WGB	140
7.5.2.15	LSPMAC_DPASCII_QUEUE_LENGTH	140
7.5.2.16	LSPMAC_MAX_MOTORS	140
7.5.2.17	LSPMAC_PRESET_REGEX	140
7.5.2.18	PMAC_CMD_QUEUE_LENGTH	141
7.5.2.19	pmac_cmd_size	141
7.5.2.20	PMAC_MIN_CMD_TIME	141
7.5.2.21	PMACPORT	141
7.5.2.22	VR_CTRL_RESPONSE	141
7.5.2.23	VR_DOWNLOAD	141
7.5.2.24	VR_FWDOWNLOAD	141
7.5.2.25	VR_IPADDRESS	141
7.5.2.26	VR_PMAC_FLUSH	141
7.5.2.27	VR_PMAC_GETBUFFER	141
7.5.2.28	VR_PMAC_GETLINE	141
7.5.2.29	VR_PMAC_GETMEM	142
7.5.2.30	VR_PMAC_GETRESPONSE	142
7.5.2.31	VR_PMAC_PORT	142
7.5.2.32	VR_PMAC_READREADY	142
7.5.2.33	VR_PMAC_SENDCTRLCHAR	142
7.5.2.34	VR_PMAC_SENDLINE	142
7.5.2.35	VR_PMAC_SETBIT	142
7.5.2.36	VR_PMAC_SETBITS	142
7.5.2.37	VR_PMAC_SETMEM	142
7.5.2.38	VR_PMAC_WRITEBUFFER	142
7.5.2.39	VR_PMAC_WRITEERROR	142
7.5.2.40	VR_UPLOAD	142
7.5.3	Typedef Documentation	143
7.5.3.1	lspmac_ascii_buffers_t	143
7.5.3.2	lspmac_combined_move_t	143
7.5.3.3	lspmac_dpascii_queue_t	143
7.5.3.4	md2_status_t	143
7.5.4	Function Documentation	143
7.5.4.1	_lspmac_motor_init	143
7.5.4.2	cleanstr	144

7.5.4.3	hex_dump	144
7.5.4.4	IsConnect	145
7.5.4.5	lspmac_abort	146
7.5.4.6	lspmac_asciicmdCB	146
7.5.4.7	lspmac_backLight_down_cb	146
7.5.4.8	lspmac_backLight_up_cb	146
7.5.4.9	lspmac_bi_init	147
7.5.4.10	lspmac_blight_lut_setup	147
7.5.4.11	lspmac_bo_init	148
7.5.4.12	lspmac_bo_read	148
7.5.4.13	lspmac_command_done_cb	148
7.5.4.14	lspmac_cryoSwitchChanged_cb	149
7.5.4.15	lspmac_dac_init	149
7.5.4.16	lspmac_dac_read	150
7.5.4.17	lspmac_Error	150
7.5.4.18	lspmac_est_move_time	151
7.5.4.19	lspmac_est_move_time_wait	155
7.5.4.20	lspmac_find_motor_by_name	156
7.5.4.21	lspmac_flight_lut_setup	157
7.5.4.22	lspmac_fscint_lut_setup	157
7.5.4.23	lspmac_fshut_init	157
7.5.4.24	lspmac_get_ascii	158
7.5.4.25	lspmac_get_ascii_cb	158
7.5.4.26	lspmac_get_status	160
7.5.4.27	lspmac_get_status_cb	160
7.5.4.28	lspmac_GetAllIVars	163
7.5.4.29	lspmac_GetAllIVarsCB	163
7.5.4.30	lspmac_GetAllMVars	163
7.5.4.31	lspmac_GetAllMVarsCB	164
7.5.4.32	lspmac_getBIPosition	164
7.5.4.33	lspmac_Getmem	164
7.5.4.34	lspmac_GetmemReplyCB	164
7.5.4.35	lspmac_getPosition	165
7.5.4.36	lspmac_GetShortReplyCB	165
7.5.4.37	lspmac_home1_queue	166
7.5.4.38	lspmac_home2_queue	167
7.5.4.39	lspmac_init	167
7.5.4.40	lspmac_jogabs_queue	171
7.5.4.41	lspmac_light_zoom_cb	171
7.5.4.42	lspmac_lut	172

7.5.4.43	lspmac_more_ascii_cb	173
7.5.4.44	lspmac_motor_init	173
7.5.4.45	lspmac_move_or_jog_abs_queue	174
7.5.4.46	lspmac_move_or_jog_preset_queue	177
7.5.4.47	lspmac_move_preset_queue	177
7.5.4.48	lspmac_moveabs_blight_factor_queue	178
7.5.4.49	lspmac_moveabs_bo_queue	178
7.5.4.50	lspmac_moveabs_flight_factor_queue	179
7.5.4.51	lspmac_moveabs_frontlight_oo_queue	179
7.5.4.52	lspmac_moveabs_fshut_queue	179
7.5.4.53	lspmac_moveabs_queue	180
7.5.4.54	lspmac_moveabs_timed_queue	180
7.5.4.55	lspmac_moveabs_wait	181
7.5.4.56	lspmac_movedac_queue	182
7.5.4.57	lspmac_movezoom_queue	183
7.5.4.58	lspmac_next_state	184
7.5.4.59	lspmac_pmacmotor_read	185
7.5.4.60	lspmac_pop_queue	188
7.5.4.61	lspmac_pop_reply	189
7.5.4.62	lspmac_push_queue	189
7.5.4.63	lspmac_Reset	189
7.5.4.64	lspmac_reset_queue	190
7.5.4.65	lspmac_rlut	190
7.5.4.66	lspmac_run	191
7.5.4.67	lspmac_scint_dried_cb	192
7.5.4.68	lspmac_scint_maybe_move_sample_cb	193
7.5.4.69	lspmac_scint_maybe_return_sample_cb	193
7.5.4.70	lspmac_scint_maybe_turn_off_dryer_cb	194
7.5.4.71	lspmac_scint_maybe_turn_on_dryer_cb	194
7.5.4.72	lspmac_send_command	195
7.5.4.73	lspmac_sendcmd	195
7.5.4.74	lspmac_sendcmd_nocb	196
7.5.4.75	lspmac_SendControlReplyPrintCB	196
7.5.4.76	lspmac_Service	197
7.5.4.77	lspmac_set_motion_flags	199
7.5.4.78	lspmac_shutter_read	200
7.5.4.79	lspmac_SockFlush	201
7.5.4.80	lspmac_SockGetmem	201
7.5.4.81	lspmac_SockSendControlCharPrint	201
7.5.4.82	lspmac_SockSendDPControlChar	202

7.5.4.83	lspmac_SockSendDPControlCharCB	202
7.5.4.84	lspmac_SockSendDPLine	202
7.5.4.85	lspmac_SockSendDPqueue	202
7.5.4.86	lspmac_SockSendline	203
7.5.4.87	lspmac_SockSendline_nr	203
7.5.4.88	lspmac_soft_motor_init	204
7.5.4.89	lspmac_soft_motor_read	204
7.5.4.90	lspmac_test_preset	204
7.5.4.91	lspmac_video_rotate	204
7.5.4.92	lspmac_worker	205
7.5.4.93	lspmac_zoom_lut_setup	206
7.5.5	Variable Documentation	206
7.5.5.1	alignx	206
7.5.5.2	aligny	206
7.5.5.3	alignz	206
7.5.5.4	anal	207
7.5.5.5	apery	207
7.5.5.6	aperz	207
7.5.5.7	arm_parked	207
7.5.5.8	blight	207
7.5.5.9	blight_down	207
7.5.5.10	blight_f	207
7.5.5.11	blight_ud	207
7.5.5.12	blight_up	207
7.5.5.13	capy	208
7.5.5.14	capz	208
7.5.5.15	cenx	208
7.5.5.16	ceny	208
7.5.5.17	cr_cmd	208
7.5.5.18	cryo	208
7.5.5.19	cryo_back	208
7.5.5.20	cryo_switch	208
7.5.5.21	dbmem	208
7.5.5.22	dbmemIn	209
7.5.5.23	dryer	209
7.5.5.24	etel_init_ok	209
7.5.5.25	etel_on	209
7.5.5.26	etel_ready	209
7.5.5.27	ethCmdOff	209
7.5.5.28	ethCmdOn	209

7.5.5.29	ethCmdQueue	209
7.5.5.30	ethCmdReply	209
7.5.5.31	flight	210
7.5.5.32	flight_f	210
7.5.5.33	flight_oo	210
7.5.5.34	fluo	210
7.5.5.35	fluor_back	210
7.5.5.36	fscint	210
7.5.5.37	fshut	210
7.5.5.38	gb_cmd	210
7.5.5.39	getivars	210
7.5.5.40	getmvars	211
7.5.5.41	hp_air	211
7.5.5.42	kappa	211
7.5.5.43	lp_air	211
7.5.5.44	ls_pmac_state	211
7.5.5.45	lspmac_ascii_buffers	211
7.5.5.46	lspmac_ascii_buffers_mutex	211
7.5.5.47	lspmac_ascii_busy	211
7.5.5.48	lspmac_ascii_mutex	211
7.5.5.49	lspmac_bis	211
7.5.5.50	lspmac_dpascii_off	212
7.5.5.51	lspmac_dpascii_on	212
7.5.5.52	lspmac_dpascii_queue	212
7.5.5.53	lspmac_motors	212
7.5.5.54	lspmac_moving_cond	212
7.5.5.55	lspmac_moving_flags	212
7.5.5.56	lspmac_moving_mutex	212
7.5.5.57	lspmac_nbis	212
7.5.5.58	lspmac_nmotors	212
7.5.5.59	lspmac_shutter_cond	212
7.5.5.60	lspmac_shutter_has_opened	213
7.5.5.61	lspmac_shutter_mutex	213
7.5.5.62	lspmac_shutter_state	213
7.5.5.63	lspmac_status_last_time	213
7.5.5.64	lspmac_status_time	213
7.5.5.65	md2_status	213
7.5.5.66	md2_status_mutex	213
7.5.5.67	minikappa_ok	213
7.5.5.68	motors_ht	213

7.5.5.69	now	214
7.5.5.70	omega	214
7.5.5.71	omega_zero_search	214
7.5.5.72	omega_zero_time	214
7.5.5.73	omega_zero_velocity	214
7.5.5.74	phi	214
7.5.5.75	pmac_error_strs	214
7.5.5.76	pmac_queue_cond	215
7.5.5.77	pmac_queue_mutex	215
7.5.5.78	pmac_thread	215
7.5.5.79	pmacfd	215
7.5.5.80	rr_cmd	215
7.5.5.81	sample_detected	215
7.5.5.82	scint	215
7.5.5.83	shutter_open	215
7.5.5.84	smart_mag_err	215
7.5.5.85	smart_mag_off	216
7.5.5.86	smart_mag_on	216
7.5.5.87	smart_mag_oo	216
7.5.5.88	zoom	216
7.6	Isredis.c File Reference	216
7.6.1	Detailed Description	218
7.6.2	Typedef Documentation	219
7.6.2.1	Isredis_preset_list_t	219
7.6.3	Function Documentation	219
7.6.3.1	_Isredis_get_obj	219
7.6.3.2	_Isredis_set_value	220
7.6.3.3	Isredis_addRead	221
7.6.3.4	Isredis_addWrite	221
7.6.3.5	Isredis_cleanup	222
7.6.3.6	Isredis_cmpnstr	222
7.6.3.7	Isredis_cmpstr	222
7.6.3.8	Isredis_debugCB	222
7.6.3.9	Isredis_delRead	223
7.6.3.10	Isredis_delWrite	223
7.6.3.11	Isredis_fd_service	224
7.6.3.12	Isredis_find_preset	224
7.6.3.13	Isredis_find_preset_index_by_position	225
7.6.3.14	Isredis_get_obj	225
7.6.3.15	Isredis_get_or_set_d	225

7.6.3.16	lsredis_get_or_set_l	226
7.6.3.17	lsredis_get_string_array	226
7.6.3.18	lsredis_getb	226
7.6.3.19	lsredis_getc	227
7.6.3.20	lsredis_getd	227
7.6.3.21	lsredis_getl	227
7.6.3.22	lsredis_getstr	227
7.6.3.23	lsredis_hgetCB	228
7.6.3.24	lsredis_init	228
7.6.3.25	lsredis_keysCB	229
7.6.3.26	lsredis_load_presets	230
7.6.3.27	lsredis_maybe_add_key	231
7.6.3.28	lsredis_regexec	231
7.6.3.29	lsredis_run	231
7.6.3.30	lsredis_set_preset	232
7.6.3.31	lsredis_set_value	232
7.6.3.32	lsredis_setstr	233
7.6.3.33	lsredis_sig_service	233
7.6.3.34	lsredis_subCB	234
7.6.3.35	lsredis_worker	235
7.6.3.36	redisDisconnectCB	236
7.6.4	Variable Documentation	236
7.6.4.1	lsredis_cond	236
7.6.4.2	lsredis_head	236
7.6.4.3	lsredis_htab	237
7.6.4.4	lsredis_key_select_regex	237
7.6.4.5	lsredis_mutex	237
7.6.4.6	lsredis_objs	237
7.6.4.7	lsredis_preset_ht	237
7.6.4.8	lsredis_preset_list	237
7.6.4.9	lsredis_preset_list_mutex	237
7.6.4.10	lsredis_preset_max_n	237
7.6.4.11	lsredis_preset_n	237
7.6.4.12	lsredis_publisher	237
7.6.4.13	lsredis_running	237
7.6.4.14	lsredis_thread	237
7.6.4.15	roac	238
7.6.4.16	rofd	238
7.6.4.17	subac	238
7.6.4.18	subfd	238

7.6.4.19	wrac	238
7.6.4.20	wrfd	238
7.7	ltest.c File Reference	238
7.7.1	Function Documentation	238
7.7.1.1	ltest_lspmac_est_move_time	238
7.7.1.2	ltest_main	240
7.8	ltimer.c File Reference	240
7.8.1	Detailed Description	241
7.8.2	Macro Definition Documentation	241
7.8.2.1	LSTIMER_LIST_LENGTH	241
7.8.2.2	LSTIMER_RESOLUTION_NSECS	242
7.8.3	Typedef Documentation	242
7.8.3.1	ltimer_list_t	242
7.8.4	Function Documentation	242
7.8.4.1	handler	242
7.8.4.2	ltimer_init	242
7.8.4.3	ltimer_run	242
7.8.4.4	ltimer_set_timer	242
7.8.4.5	ltimer_unset_timer	243
7.8.4.6	ltimer_worker	244
7.8.4.7	service_timers	245
7.8.5	Variable Documentation	246
7.8.5.1	ltimer_active_timers	246
7.8.5.2	ltimer_cond	246
7.8.5.3	ltimer_list	246
7.8.5.4	ltimer_mutex	246
7.8.5.5	ltimer_thread	246
7.8.5.6	ltimer_timerid	246
7.8.5.7	new_timer	246
7.9	md2cmds.c File Reference	246
7.9.1	Detailed Description	249
7.9.2	Typedef Documentation	249
7.9.2.1	md2cmds_cmd_kv_t	249
7.9.3	Function Documentation	249
7.9.3.1	md2cmds_abort	249
7.9.3.2	md2cmds_action_queue	250
7.9.3.3	md2cmds_action_wait	250
7.9.3.4	md2cmds_center	250
7.9.3.5	md2cmds_collect	251
7.9.3.6	md2cmds_coordsys_1_stopped_cb	255

7.9.3.7	md2cmds_coordsys_2_stopped_cb	255
7.9.3.8	md2cmds_coordsys_3_stopped_cb	255
7.9.3.9	md2cmds_coordsys_4_stopped_cb	255
7.9.3.10	md2cmds_coordsys_5_stopped_cb	255
7.9.3.11	md2cmds_coordsys_7_stopped_cb	256
7.9.3.12	md2cmds_home_prep	256
7.9.3.13	md2cmds_home_wait	256
7.9.3.14	md2cmds_init	256
7.9.3.15	md2cmds_is_moving	257
7.9.3.16	md2cmds_kappaphi_move	257
7.9.3.17	md2cmds_maybe_done_homing_cb	258
7.9.3.18	md2cmds_maybe_done_moving_cb	258
7.9.3.19	md2cmds_maybe_rotate_done_cb	259
7.9.3.20	md2cmds_move_prep	259
7.9.3.21	md2cmds_move_wait	259
7.9.3.22	md2cmds_moveAbs	260
7.9.3.23	md2cmds_moveRel	261
7.9.3.24	md2cmds_mvcenter_move	262
7.9.3.25	md2cmds_organs_move_presets	262
7.9.3.26	md2cmds_phase_beamLocation	263
7.9.3.27	md2cmds_phase_center	264
7.9.3.28	md2cmds_phase_change	265
7.9.3.29	md2cmds_phase_dataCollection	266
7.9.3.30	md2cmds_phase_manualMount	266
7.9.3.31	md2cmds_phase_robotMount	267
7.9.3.32	md2cmds_phase_safe	268
7.9.3.33	md2cmds_prep_axis	268
7.9.3.34	md2cmds_rotate	269
7.9.3.35	md2cmds_rotate_cb	271
7.9.3.36	md2cmds_run	271
7.9.3.37	md2cmds_run_cmd	272
7.9.3.38	md2cmds_set	272
7.9.3.39	md2cmds_set_scale_cb	273
7.9.3.40	md2cmds_settransferpoint	274
7.9.3.41	md2cmds_test	274
7.9.3.42	md2cmds_time_capz_cb	275
7.9.3.43	md2cmds_transfer	275
7.9.3.44	md2cmds_worker	278
7.9.4	Variable Documentation	278
7.9.4.1	md2cmds_capz_moving_time	278

7.9.4.2	md2cmds_cmd	279
7.9.4.3	md2cmds_cmd_kvs	279
7.9.4.4	md2cmds_cmd_regex	279
7.9.4.5	md2cmds_cond	279
7.9.4.6	md2cmds_hmap	279
7.9.4.7	md2cmds_homing_cond	279
7.9.4.8	md2cmds_homing_count	279
7.9.4.9	md2cmds_homing_mutex	279
7.9.4.10	md2cmds_md_status_code	280
7.9.4.11	md2cmds_moving_cond	280
7.9.4.12	md2cmds_moving_count	280
7.9.4.13	md2cmds_moving_mutex	280
7.9.4.14	md2cmds_moving_queue_wait	280
7.9.4.15	md2cmds_mutex	280
7.9.4.16	md2cmds_thread	280
7.9.4.17	rotating	280
7.10	mk_pgpmac_redis.py File Reference	280
7.11	pgpmac.c File Reference	281
7.11.1	Detailed Description	282
7.11.2	Function Documentation	282
7.11.2.1	main	282
7.11.2.2	pgpmac_printf	284
7.11.2.3	stdinService	284
7.11.3	Variable Documentation	285
7.11.3.1	ncurses_mutex	285
7.11.3.2	running	285
7.11.3.3	stdinfda	285
7.11.3.4	term_input	286
7.11.3.5	term_output	286
7.11.3.6	term_status	286
7.11.3.7	term_status2	286
7.12	pgpmac.h File Reference	286
7.12.1	Detailed Description	294
7.12.2	Macro Definition Documentation	294
7.12.2.1	_GNU_SOURCE	294
7.12.2.2	LS_DISPLAY_WINDOW_HEIGHT	294
7.12.2.3	LS_DISPLAY_WINDOW_WIDTH	294
7.12.2.4	LS_PG_QUERY_STRING_LENGTH	294
7.12.2.5	LSEVENTS_EVENT_LENGTH	294
7.12.2.6	LSPMAC_MAGIC_NUMBER	295

7.12.2.7	MD2CMDS_CMD_LENGTH	295
7.12.3	Typedef Documentation	295
7.12.3.1	lspg_demandairrights_t	295
7.12.3.2	lspg_getcenter_t	295
7.12.3.3	lspg_getcurrentsampleid_t	295
7.12.3.4	lspg_nextsample_t	295
7.12.3.5	lspg_nextshot_t	295
7.12.3.6	lspg_query_queue_t	295
7.12.3.7	lspg_starttransfer_t	295
7.12.3.8	lspg_waitcryo_t	295
7.12.3.9	lspmac_bi_t	295
7.12.3.10	lspmac_motor_t	295
7.12.3.11	lsredis_obj_t	296
7.12.3.12	pmac_cmd_queue_t	296
7.12.3.13	pmac_cmd_t	296
7.12.4	Function Documentation	296
7.12.4.1	_lsredis_get_obj	296
7.12.4.2	lsevents_add_listener	297
7.12.4.3	lsevents_init	298
7.12.4.4	lsevents_preregister_event	298
7.12.4.5	lsevents_remove_listener	299
7.12.4.6	lsevents_run	299
7.12.4.7	lsevents_send_event	300
7.12.4.8	lslogging_init	300
7.12.4.9	lslogging_log_message	300
7.12.4.10	lslogging_run	301
7.12.4.11	lspg_array2ptrs	301
7.12.4.12	lspg_demandairrights_all	303
7.12.4.13	lspg_getcenter_call	303
7.12.4.14	lspg_getcenter_done	303
7.12.4.15	lspg_getcenter_wait	303
7.12.4.16	lspg_getcurrentsampleid_wait_for_id	304
7.12.4.17	lspg_init	304
7.12.4.18	lspg_nextsample_all	304
7.12.4.19	lspg_nextshot_call	304
7.12.4.20	lspg_nextshot_done	305
7.12.4.21	lspg_nextshot_wait	305
7.12.4.22	lspg_query_push	305
7.12.4.23	lspg_run	306
7.12.4.24	lspg_seq_run_prep_all	306

7.12.4.25 lspg_starttransfer_call	306
7.12.4.26 lspg_starttransfer_done	307
7.12.4.27 lspg_starttransfer_wait	307
7.12.4.28 lspg_waitcryo_all	307
7.12.4.29 lspg_waitcryo_cb	307
7.12.4.30 lspg_zoom_lut_call	308
7.12.4.31 lspmac_abort	308
7.12.4.32 lspmac_est_move_time	308
7.12.4.33 lspmac_est_move_time_wait	313
7.12.4.34 lspmac_find_motor_by_name	314
7.12.4.35 lspmac_getBIPosition	314
7.12.4.36 lspmac_getPosition	314
7.12.4.37 lspmac_home1_queue	315
7.12.4.38 lspmac_home2_queue	316
7.12.4.39 lspmac_init	316
7.12.4.40 lspmac_jogabs_queue	320
7.12.4.41 lspmac_move_or_jog_abs_queue	320
7.12.4.42 lspmac_move_or_jog_preset_queue	323
7.12.4.43 lspmac_move_or_jog_queue	324
7.12.4.44 lspmac_move_preset_queue	324
7.12.4.45 lspmac_moveabs_queue	324
7.12.4.46 lspmac_moveabs_wait	324
7.12.4.47 lspmac_run	325
7.12.4.48 lspmac_set_motion_flags	327
7.12.4.49 lspmac_SockSendDPControlChar	328
7.12.4.50 lspmac_SockSendDPLine	328
7.12.4.51 lspmac_SockSendline	329
7.12.4.52 lspmac_video_rotate	329
7.12.4.53 lsredis_cmpnstr	330
7.12.4.54 lsredis_cmpstr	330
7.12.4.55 lsredis_find_preset	330
7.12.4.56 lsredis_find_preset_index_by_position	331
7.12.4.57 lsredis_get_obj	331
7.12.4.58 lsredis_get_string_array	332
7.12.4.59 lsredis_getb	332
7.12.4.60 lsredis_getc	332
7.12.4.61 lsredis_getd	332
7.12.4.62 lsredis_getl	333
7.12.4.63 lsredis_getstr	333
7.12.4.64 lsredis_init	333

7.12.4.65	lsredis_load_presets	334
7.12.4.66	lsredis_regex	335
7.12.4.67	lsredis_run	336
7.12.4.68	lsredis_set_preset	336
7.12.4.69	lsredis_setstr	336
7.12.4.70	lstest_main	337
7.12.4.71	lstimer_init	337
7.12.4.72	lstimer_run	338
7.12.4.73	lstimer_set_timer	338
7.12.4.74	lstimer_unset_timer	339
7.12.4.75	lsupdate_init	339
7.12.4.76	lsupdate_run	339
7.12.4.77	md2cmds_init	339
7.12.4.78	md2cmds_run	340
7.12.4.79	pgpmac_printf	340
7.12.4.80	PmacSockSendline	341
7.12.5	Variable Documentation	341
7.12.5.1	alignx	341
7.12.5.2	aligny	341
7.12.5.3	alignz	341
7.12.5.4	anal	341
7.12.5.5	apery	341
7.12.5.6	aperz	341
7.12.5.7	arm_parked	342
7.12.5.8	blight	342
7.12.5.9	blight_down	342
7.12.5.10	blight_f	342
7.12.5.11	blight_ud	342
7.12.5.12	blight_up	342
7.12.5.13	capy	342
7.12.5.14	capz	342
7.12.5.15	cenx	342
7.12.5.16	ceny	343
7.12.5.17	cryo	343
7.12.5.18	cryo_back	343
7.12.5.19	cryo_switch	343
7.12.5.20	dryer	343
7.12.5.21	etel_init_ok	343
7.12.5.22	etel_on	343
7.12.5.23	etel_ready	343

7.12.5.24 flight	343
7.12.5.25 flight_f	344
7.12.5.26 flight_oo	344
7.12.5.27 fluo	344
7.12.5.28 fluor_back	344
7.12.5.29 fscint	344
7.12.5.30 fshut	344
7.12.5.31 hp_air	344
7.12.5.32 kappa	344
7.12.5.33 lp_air	344
7.12.5.34 lspg_demandairrights	345
7.12.5.35 lspg_getcenter	345
7.12.5.36 lspg_getcurrentsampleid	345
7.12.5.37 lspg_nextsample	345
7.12.5.38 lspg_nextshot	345
7.12.5.39 lspg_starttransfer	345
7.12.5.40 lspg_waitcryo	345
7.12.5.41 lspmac_motors	345
7.12.5.42 lspmac_moving_cond	345
7.12.5.43 lspmac_moving_flags	346
7.12.5.44 lspmac_moving_mutex	346
7.12.5.45 lspmac_nmotors	346
7.12.5.46 lspmac_shutter_cond	346
7.12.5.47 lspmac_shutter_has_opened	346
7.12.5.48 lspmac_shutter_mutex	346
7.12.5.49 lspmac_shutter_state	346
7.12.5.50 lsredis_cond	346
7.12.5.51 lsredis_mutex	346
7.12.5.52 lsredis_running	346
7.12.5.53 md2_status_mutex	347
7.12.5.54 md2cmds_cmd	347
7.12.5.55 md2cmds_cond	347
7.12.5.56 md2cmds_md_status_code	347
7.12.5.57 md2cmds_mutex	347
7.12.5.58 md2cmds_pg_cond	347
7.12.5.59 md2cmds_pg_mutex	347
7.12.5.60 minikappa_ok	347
7.12.5.61 ncurses_mutex	347
7.12.5.62 omega	347
7.12.5.63 omega_zero_time	347

7.12.5.64 phi	348
7.12.5.65 pmac_queue_cond	348
7.12.5.66 pmac_queue_mutex	348
7.12.5.67 sample_detected	348
7.12.5.68 scint	348
7.12.5.69 shutter_open	348
7.12.5.70 smart_mag_err	348
7.12.5.71 smart_mag_off	348
7.12.5.72 smart_mag_on	348
7.12.5.73 smart_mag_oo	349
7.12.5.74 term_input	349
7.12.5.75 term_output	349
7.12.5.76 term_status	349
7.12.5.77 term_status2	349
7.12.5.78 zoom	349

Index**349**

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

Namespace Index

2.1 Namespace List

Here is a list of all namespaces with brief descriptions:

iniParser	11
mk_pgpmac_redis	11

Chapter 3

Data Structure Index

3.1 Data Structures

Here are the data structures with brief descriptions:

iniParser.iniParser	This program is free software: you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation, either version 3 of the License, or (at your option) any later version	15
lsevents_callbacks_struct	Lsevents linked list of callbacks for each event	17
lsevents_event_names_struct	Linked list of all the event names used to regenerate the hash table	18
lsevents_listener_struct	Linked list of event listeners	19
lsevents_queue_struct	Storage definition for the events	20
lsllogging_queue_struct	Our log object: time and message	20
lspg_demandairrights_struct	21
lspg_getcenter_struct	Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies	22
lspg_getcurrentsampleid_struct	24
lspg_lock_detector_struct	Lock detector object Implements detector lock for exposure control	25
lspg_lock_diffractionmeter_struct	Object used to impliment locking the diffractometer Critical to exposure timing	26
lspg_nextsample_struct	Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)	27
lspg_nextshot_struct	Storage definition for nextshot query	28
lspg_seq_run_prep_struct	Data collection running object	39
lspg_starttransfer_struct	Returns 1 if transfer can continue 0 to abort	40
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	41
lspg_waitcryo_struct	41
lspgQueryQueueStruct	Store each query along with it's callback function	42
lspmac_asci_buffers_struct	43

lspmac_bi_struct	
Storage for binary inputs	44
lspmac_cmd_queue_struct	
PMAC command queue item	46
lspmac_combined_move_struct	47
lspmac_dpascii_queue_struct	47
lspmac_motor_struct	
Motor information	48
lsredis_obj_struct	
Redis Object Basic object whose value is sychronized with our redis db	56
lsredis_preset_list_struct	59
lstimer_list_struct	
Everything we need to know about a timer	60
md2cmds_cmd_kv_struct	62
md2StatusStruct	
The block of memory retrieved in a status request	62
tagEthernetCmd	
PMAC ethernet packet definition	70

Chapter 4

File Index

4.1 File List

Here is a list of all files with brief descriptions:

iniParser.py	73
lsevents.c	
Event subsystem for inter-pgpmac communication	73
lslogging.c	
Logs messages to a file	82
lspg.c	
Postgresql support for the LS-CAT pgpmac project	86
lspmac.c	
Routines concerned with communication with PMAC	130
lsredis.c	
Support redis hash synchronization	216
lstest.c	238
lstimer.c	
Support for delayed and periodic events	240
md2cmds.c	
Implements commands to run the md2 diffractometer attached to a PMAC controled by post- gresql	246
mk_pgpmac_redis.py	280
pgpmac.c	
Main for the pgpmac project	281
pgpmac.h	
Headers for the entire pgpmac project	286

Chapter 5

Namespace Documentation

5.1 iniParser Namespace Reference

Data Structures

- class [iniParser](#)

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Variables

- tuple [ip iniParser](#)("21-ID-E/microdiff_hard.ini")

5.1.1 Variable Documentation

5.1.1.1 tuple [iniParser.ip iniParser](#)("21-ID-E/microdiff_hard.ini")

Definition at line 104 of file [iniParser.py](#).

5.2 mk_pgpmac_redis Namespace Reference

Functions

- def [active_simulation](#)
- def [asis](#)

Variables

- list [head](#) sys.argv[1]
- list [pref_ini](#) sys.argv[2]
- list [hard_ini](#) sys.argv[3]
- dictionary [motor_dict](#)
- dictionary [hard_ini_fields](#)
- list [motor_field_lists](#)
- list [bi_list](#) ["CryoSwitch"]
- dictionary [motor_presets](#)

- list `zoom_settings`
- tuple `hi iniParser.iniParser(hard_ini)`
- list `v motor_dict[m]`
- string `f "HSETNX"`
- list `xlate hard_ini_fields[k]`
- tuple `pi iniParser.iniParser(pref_ini)`
- int `i 0`
- tuple `ppos pi.get(section, option)`
- string `fnc "HSETNX"`
- tuple `b pi.get(section, "LightIntensity")`
- tuple `p pi.get(section, "MotorPosition")`
- tuple `x pi.get(section, "ScaleX")`
- tuple `y pi.get(section, "ScaleY")`

5.2.1 Function Documentation

5.2.1.1 `def mk_pgpmac_redis.active_simulation(sim)`

Definition at line 172 of file `mk_pgpmac_redis.py`.

```

172
173 def active_simulation( sim):
174     if str(sim) != "0":
175         rtn = "0"
176     else:
177         rtn = "1"
178     return rtn

```

5.2.1.2 `def mk_pgpmac_redis.asis(arg)`

Definition at line 179 of file `mk_pgpmac_redis.py`.

```

179
180 def asis( arg):
181     return arg

```

5.2.2 Variable Documentation

5.2.2.1 `tuple mk_pgpmac_redis.b pi.get(section, "LightIntensity")`

Definition at line 425 of file `mk_pgpmac_redis.py`.

5.2.2.2 `list mk_pgpmac_redis.bi_list ["CryoSwitch"]`

Definition at line 243 of file `mk_pgpmac_redis.py`.

5.2.2.3 `tuple mk_pgpmac_redis.f "HSETNX"`

Definition at line 366 of file `mk_pgpmac_redis.py`.

5.2.2.4 `string mk_pgpmac_redis.fnc "HSETNX"`

Definition at line 416 of file `mk_pgpmac_redis.py`.

5.2.2.5 mk_pgpmac_redis.hard_ini sys.argv[3]

Definition at line 21 of file mk_pgpmac_redis.py.

5.2.2.6 dictionary mk_pgpmac_redis.hard_ini_fields

Initial value:

```

1 {
2     "active"           : ["Simulation", active_simulation],
3     "coord_num"        : ["CoordinateSystem", asis],
4     "largeStep"        : ["LargeStep", asis],
5     "maxPosition"      : ["MaxPosition", asis],
6     "minPosition"      : ["MinPosition", asis],
7     "motor_num"        : ["MotorNumber", asis],
8     "neutralPosition"  : ["NeutralPosition", asis],
9     "precision"        : ["Precision", asis],
10    "smallStep"        : ["SmallStep", asis],
11    "u2c"              : ["UnitRatio", asis]
12 }
```

Definition at line 182 of file mk_pgpmac_redis.py.

5.2.2.7 list mk_pgpmac_redis.head sys.argv[1]

Definition at line 13 of file mk_pgpmac_redis.py.

5.2.2.8 tuple mk_pgpmac_redis.hi iniParser.iniParser(hard_ini)

Definition at line 336 of file mk_pgpmac_redis.py.

5.2.2.9 int mk_pgpmac_redis.i 0

Definition at line 390 of file mk_pgpmac_redis.py.

5.2.2.10 dictionary mk_pgpmac_redis.motor_dict

Definition at line 29 of file mk_pgpmac_redis.py.

5.2.2.11 list mk_pgpmac_redis.motor_field_lists

Definition at line 204 of file mk_pgpmac_redis.py.

5.2.2.12 dictionary mk_pgpmac_redis.motor_presets

Definition at line 245 of file mk_pgpmac_redis.py.

5.2.2.13 tuple mk_pgpmac_redis.p pi.get(section, "MotorPosition")

Definition at line 432 of file mk_pgpmac_redis.py.

5.2.2.14 tuple mk_pgpmac_redis.pi iniParser.iniParser(pref_ini)

Definition at line 387 of file mk_pgpmac_redis.py.

5.2.2.15 tuple mk_pgpmac_redis.ppos pi.get(section, option)

Definition at line 398 of file mk_pgpmac_redis.py.

5.2.2.16 mk_pgpmac_redis.pref_ini sys.argv[2]

Definition at line 16 of file mk_pgpmac_redis.py.

5.2.2.17 tuple mk_pgpmac_redis.v motor_dict[m]

Definition at line 365 of file mk_pgpmac_redis.py.

5.2.2.18 tuple mk_pgpmac_redis.x pi.get(section, "ScaleX")

Definition at line 439 of file mk_pgpmac_redis.py.

5.2.2.19 list mk_pgpmac_redis.xlate hard_ini_fields[k]

Definition at line 370 of file mk_pgpmac_redis.py.

5.2.2.20 tuple mk_pgpmac_redis.y pi.get(section, "ScaleY")

Definition at line 446 of file mk_pgpmac_redis.py.

5.2.2.21 list mk_pgpmac_redis.zoom_settings

Initial value:

```

1 [
2   #lev  front  back  pos      scalex  scaley  section
3   [1,    4.0,   8.0,   34100,  2.7083,  3.3442, "CoaxCam.Zoom1"],
4   [2,    6.0,   8.1,   31440,  2.2487,  2.2776, "CoaxCam.Zoom2"],
5   [3,    6.5,   8.2,   27460,  1.7520,  1.7550, "CoaxCam.Zoom3"],
6   [4,    7.0,   8.3,   23480,  1.3360,  1.3400, "CoaxCam.Zoom4"],
7   [5,    8.0,   10.0,  19500,  1.0140,  1.0110, "CoaxCam.Zoom5"],
8   [6,    9.0,   12.0,  15520,  0.7710,  0.7760, "CoaxCam.Zoom6"],
9   [7,   10.0,   17.0,  11540,  0.5880,  0.5920, "CoaxCam.Zoom7"],
10  [8,   12.0,   25.0,   7560,  0.4460,  0.4480, "CoaxCam.Zoom8"],
11  [9,   15.0,   37.0,   3580,  0.3410,  0.3460, "CoaxCam.Zoom9"],
12  [10,  16.0,   42.0,    0,  0.2700,  0.2690, "CoaxCam.Zoom10"]
13 ]

```

Definition at line 312 of file mk_pgpmac_redis.py.

Chapter 6

Data Structure Documentation

6.1 iniParser.iniParser Class Reference

This program is free software: you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation, either version 3 of the License, or (at your option) any later version.

Public Member Functions

- def `__init__`
- def `read`
- def `sections`
- def `options`
- def `has_section`
- def `has_option`
- def `get`

Data Fields

- `f`
- `sd`

6.1.1 Detailed Description

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We assume the sections and options are case insensitive and that, although nested sections are implied by the format used by the md2, that the nesting has no practical importance.

The current version is for READING the files.

TODO: add writing. We'll need to keep track of the preferred case used in the ini file as well as the existing comments. This is mildly tricky since comments apparently can appear on both option lines and non-option lines so

we'll need to track the line number within each section to preserve all the comments. Strictly speaking this is not necessary as we can just spit stuff out all lower case without comments and, presumably, the md2 should be able to deal with it. However, there is enough of a problem with the lack of documentation that willfully removing seems like a bad idea.

Definition at line 42 of file iniParser.py.

6.1.2 Constructor & Destructor Documentation

6.1.2.1 `def iniParser.iniParser.__init__(self, fn)`

Definition at line 44 of file iniParser.py.

```
44
45     def __init__( self, fn):
46         self.f = open( fn, "r")
47         self.sd = {}
48
```

6.1.3 Member Function Documentation

6.1.3.1 `def iniParser.iniParser.get(self, section, option)`

Definition at line 99 of file iniParser.py.

```
99
100     def get( self, section, option):
101         return self.sd[section.lower()][option.lower()]
102
```

6.1.3.2 `def iniParser.iniParser.has_option(self, section, option)`

Definition at line 94 of file iniParser.py.

```
94
95     def has_option( self, section, option):
96         if self.has_section( section):
97             return self.sd[section.lower()].has_key( option.lower())
98         return False
```

6.1.3.3 `def iniParser.iniParser.has_section(self, section)`

Definition at line 91 of file iniParser.py.

```
91
92     def has_section( self, section):
93         return self.sd.has_key( section.lower())
```

6.1.3.4 `def iniParser.iniParser.options(self, section)`

Definition at line 87 of file iniParser.py.

```
87
88     def options( self, section):
89         return self.sd[section.lower()].keys()
90
```

6.1.3.5 `def iniParser.iniParser.read (self)`

Definition at line 49 of file `iniParser.py`.

```

49
50     def read( self):
51         self.sd = {}
52         current_section = "default"
53         current_dict = {}
54         for l in self.f.readlines():
55             sl = l.strip()
56             if len(sl) > 0:
57                 if sl[0] == ";":
58                     continue
59
60                 if sl[0] == "[" and sl.find("]") > 1:
61                     self.sd[current_section] = current_dict
62                     current_dict = {}
63                     current_section = (sl[1:sl.find(")"])).lower()
64
65                 else:
66                     if sl.find(";") > 0:
67                         s = sl[0:sl.find(";")]
68                     else:
69                         s = sl
70
71                     if s.find("=") > 0:
72                         slist = s.split("=")
73                         if len(slist) == 2:
74                             k = (slist[0].strip()).lower()
75                             v = slist[1].strip()
76                             current_dict[k] = v
77
78         self.sd[current_section] = current_dict
79
80
81         self.f.close()
82

```

6.1.3.6 `def iniParser.iniParser.sections (self)`

Definition at line 83 of file `iniParser.py`.

```

83
84     def sections( self):
85         ks = set(self.sd.keys())
86         return list(ks.difference( ["default"]))

```

6.1.4 Field Documentation

6.1.4.1 `iniParser.iniParser.f`

Definition at line 45 of file `iniParser.py`.

6.1.4.2 `iniParser.iniParser.sd`

Definition at line 46 of file `iniParser.py`.

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

- [iniParser.py](#)

6.2 Isevents_callbacks_struct Struct Reference

Isevents linked list of callbacks for each event

Data Fields

- struct [lsevents_callbacks_struct](#) * next
- void(* [cb](#))(char *)

6.2.1 Detailed Description

Lsevents linked list of callbacks for each event

Definition at line 46 of file lsevents.c.

6.2.2 Field Documentation

6.2.2.1 void(* lsevents_callbacks_struct::cb)(char *)

Definition at line 48 of file lsevents.c.

6.2.2.2 struct lsevents_callbacks_struct* lsevents_callbacks_struct::next

Definition at line 47 of file lsevents.c.

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

- [lsevents.c](#)

6.3 lsevents_event_names_struct Struct Reference

linked list of all the event names used to regenerate the hash table

Data Fields

- struct
 [lsevents_event_names_struct](#) * next
- char * [event](#)
- [lsevents_callbacks_t](#) * [cbl](#)

6.3.1 Detailed Description

linked list of all the event names used to regenerate the hash table

Definition at line 55 of file lsevents.c.

6.3.2 Field Documentation

6.3.2.1 lsevents_callbacks_t* lsevents_event_names_struct::cbl

Definition at line 58 of file lsevents.c.

6.3.2.2 char* lsevents_event_names_struct::event

Definition at line 57 of file lsevents.c.

6.3.2.3 struct lsevents_event_names_struct* lsevents_event_names_struct::next

Definition at line 56 of file lsevents.c.

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

- [lsevents.c](#)

6.4 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

6.4.1 Detailed Description

Linked list of event listeners.

Definition at line 35 of file lsevents.c.

6.4.2 Field Documentation

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

call back function

Definition at line 39 of file lsevents.c.

6.4.2.2 struct lsevents_listener_struct* lsevents_listener_struct::next

Next listener.

Definition at line 36 of file lsevents.c.

6.4.2.3 char* lsevents_listener_struct::raw_regexp

the original string sent to us

Definition at line 37 of file lsevents.c.

6.4.2.4 `regex_t lsevents_listener_struct::re`

regular expression representing listened for events

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

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

- [lsevents.c](#)

6.5 `lsevents_queue_struct` Struct Reference

Storage definition for the events.

Data Fields

- `char * evp`
name of the event

6.5.1 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`.

6.5.2 Field Documentation

6.5.2.1 `char* lsevents_queue_struct::evp`

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](#)

6.6 `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

6.6.1 Detailed Description

Our log object: time and message.

Definition at line 24 of file lslogging.c.

6.6.2 Field Documentation

6.6.2.1 char lslogging_queue_struct::lmsg[LSLOGGING_MSG_LENGTH]

our message, truncated if too long

Definition at line 26 of file lslogging.c.

6.6.2.2 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](#)

6.7 lspg_demandairrights_struct Struct Reference

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

Data Fields

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

6.7.1 Detailed Description

Definition at line 200 of file pgpmac.h.

6.7.2 Field Documentation

6.7.2.1 pthread_cond_t lspg_demandairrights_struct::cond

Definition at line 202 of file pgpmac.h.

6.7.2.2 pthread_mutex_t lspg_demandairrights_struct::mutex

Definition at line 201 of file pgpmac.h.

6.7.2.3 int lspg_demandairrights_struct::new_value_ready

Definition at line 203 of file pgpmac.h.

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

- [pgpmac.h](#)

6.8 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](#)

6.8.1 Detailed Description

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

Definition at line 214 of file pgpmac.h.

6.8.2 Field Documentation

6.8.2.1 pthread_cond_t lspg_getcenter_struct::cond

provides signaling for when the query is done

Definition at line 216 of file pgpmac.h.

6.8.2.2 double lspg_getcenter_struct::dax

alignment x change

Definition at line 229 of file pgpmac.h.

6.8.2.3 int lspg_getcenter_struct::dax_isnull

Definition at line 230 of file pgpmac.h.

6.8.2.4 double lspg_getcenter_struct::day

alignment y change

Definition at line 232 of file pgpmac.h.

6.8.2.5 int lspg_getcenter_struct::day_isnull

Definition at line 233 of file pgpmac.h.

6.8.2.6 double lspg_getcenter_struct::daz

alignment z change

Definition at line 235 of file pgpmac.h.

6.8.2.7 int lspg_getcenter_struct::daz_isnull

Definition at line 236 of file pgpmac.h.

6.8.2.8 double lspg_getcenter_struct::dcx

center x change

Definition at line 223 of file pgpmac.h.

6.8.2.9 int lspg_getcenter_struct::dcx_isnull

Definition at line 224 of file pgpmac.h.

6.8.2.10 double lspg_getcenter_struct::dcy

center y change

Definition at line 226 of file pgpmac.h.

6.8.2.11 int lspg_getcenter_struct::dcy_isnull

Definition at line 227 of file pgpmac.h.

6.8.2.12 pthread_mutex_t lspg_getcenter_struct::mutex

don't let the threads collide!

Definition at line 215 of file pgpmac.h.

6.8.2.13 int lspg_getcenter_struct::new_value_ready

used with condition

Definition at line 217 of file pgpmac.h.

6.8.2.14 int lspg_getcenter_struct::no_rows_returned

flag in case no centering information was forthcoming

Definition at line 218 of file pgpmac.h.

6.8.2.15 int lspg_getcenter_struct::zoom

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

Definition at line 220 of file pgpmac.h.

6.8.2.16 int lspg_getcenter_struct::zoom_isnull

Definition at line 221 of file pgpmac.h.

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

- [pgpmac.h](#)

6.9 lspg_getcurrentsampleid_struct Struct Reference

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

Data Fields

- pthread_mutex_t [mutex](#)
practice safe threading
- pthread_cond_t [cond](#)
for signaling
- int [no_rows_returned](#)
flag for an empty return
- int [new_value_ready](#)
OK, there is never a value, we need a variable for the conditional wait and this is what we call it everywhere else.
- unsigned int [getcurrentsampleid](#)
the sample we think is mounted on the diffractometer
- int [getcurrentsampleid_isnull](#)
the sample we think is mounted on the diffractometer

6.9.1 Detailed Description

Definition at line 188 of file pgpmac.h.

6.9.2 Field Documentation

6.9.2.1 pthread_cond_t lspg_getcurrentsampleid_struct::cond

for signaling

Definition at line 190 of file pgpmac.h.

6.9.2.2 unsigned int lspg_getcurrentsampleid_struct::getcurrentsampleid

the sample we think is mounted on the diffractometer

Definition at line 193 of file pgpmac.h.

6.9.2.3 int lspg_getcurrentsampleid_struct::getcurrentsampleid_isnull

the sample we think is mounted on the diffractometer

Definition at line 194 of file pgpmac.h.

6.9.2.4 pthread_mutex_t lspg_getcurrentsampleid_struct::mutex

practice safe threading

Definition at line 189 of file pgpmac.h.

6.9.2.5 int lspg_getcurrentsampleid_struct::new_value_ready

OK, there is never a value, we need a variable for the conditional wait and this is what we call it everywhere else.

Definition at line 192 of file pgpmac.h.

6.9.2.6 int lspg_getcurrentsampleid_struct::no_rows_returned

flag for an empty return

Definition at line 191 of file pgpmac.h.

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

- [pgpmac.h](#)

6.10 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](#)

6.10.1 Detailed Description

lock detector object Implements detector lock for exposure control

Definition at line 1073 of file lspg.c.

6.10.2 Field Documentation

6.10.2.1 pthread_cond_t lspg_lock_detector_struct::cond

Definition at line 1075 of file lspg.c.

6.10.2.2 pthread_mutex_t lspg_lock_detector_struct::mutex

Definition at line 1074 of file lspg.c.

6.10.2.3 int lspg_lock_detector_struct::new_value_ready

Definition at line 1076 of file lspg.c.

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

- [lspg.c](#)

6.11 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](#)

6.11.1 Detailed Description

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

Definition at line 1014 of file lspg.c.

6.11.2 Field Documentation

6.11.2.1 pthread_cond_t lspg_lock_diffractionmeter_struct::cond

Definition at line 1016 of file lspg.c.

6.11.2.2 pthread_mutex_t lspg_lock_diffractionmeter_struct::mutex

Definition at line 1015 of file lspg.c.

6.11.2.3 int lspg_lock_diffractionmeter_struct::new_value_ready

Definition at line 1017 of file lspg.c.

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

- [lspg.c](#)

6.12 lspg_nextsample_struct Struct Reference

Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)

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

Data Fields

- pthread_mutex_t [mutex](#)
Our mutex.
- pthread_cond_t [cond](#)
Our condition.
- int [new_value_ready](#)
flag for our condition
- int [no_rows_returned](#)
just in case, though this query should always return an integer, perhaps 0
- unsigned int [nextsample](#)
sample number (4 8-bit segments: station, dewar (lid), puck, and position in the puck)
- int [nextsample_isnull](#)
shouldn't ever be set, but if we change the logic of this call in PG then we are ready for it here.

6.12.1 Detailed Description

Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)

Definition at line 261 of file pgpmac.h.

6.12.2 Field Documentation

6.12.2.1 pthread_cond_t lspg_nextsample_struct::cond

Our condition.

Definition at line 263 of file pgpmac.h.

6.12.2.2 pthread_mutex_t lspg_nextsample_struct::mutex

Our mutex.

Definition at line 262 of file pgpmac.h.

6.12.2.3 int lspg_nextsample_struct::new_value_ready

flag for our condition

Definition at line 264 of file pgpmac.h.

6.12.2.4 unsigned int lspg_nextsample_struct::nextsample

sample number (4 8-bit segments: station, dewar (lid), puck, and position in the puck)

Definition at line 267 of file pgpmac.h.

6.12.2.5 int lspg_nextsample_struct::nextsample_isnull

shouldn't ever be set, but if we change the logic of this call in PG then we are ready for it here.

Definition at line 268 of file pgpmac.h.

6.12.2.6 int lspg_nextsample_struct::no_rows_returned

just in case, though this query should always return an integer, perhaps 0

Definition at line 265 of file pgpmac.h.

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

- [pgpmac.h](#)

6.13 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 ascillation 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](#)

6.13.1 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 281 of file pgpmac.h.

6.13.2 Field Documentation

6.13.2.1 `int lspg_nextshot_struct::active`

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

Definition at line 344 of file pgpmac.h.

6.13.2.2 `int lspg_nextshot_struct::active2`

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

Definition at line 395 of file pgpmac.h.

6.13.2.3 `int lspg_nextshot_struct::active2_isnull`

Definition at line 396 of file pgpmac.h.

6.13.2.4 `int lspg_nextshot_struct::active_isnull`

Definition at line 345 of file pgpmac.h.

6.13.2.5 `double lspg_nextshot_struct::ax`

alignment table x position

Definition at line 335 of file pgpmac.h.

6.13.2.6 `double lspg_nextshot_struct::ax2`

next image alignment x position

Definition at line 386 of file pgpmac.h.

6.13.2.7 `int lspg_nextshot_struct::ax2_isnull`

Definition at line 387 of file pgpmac.h.

6.13.2.8 `int lspg_nextshot_struct::ax_isnull`

Definition at line 336 of file pgpmac.h.

6.13.2.9 double lspg_nextshot_struct::ay

alignment table y position

Definition at line 338 of file pgpmac.h.

6.13.2.10 double lspg_nextshot_struct::ay2

next image alignment y position

Definition at line 389 of file pgpmac.h.

6.13.2.11 int lspg_nextshot_struct::ay2_isnull

Definition at line 390 of file pgpmac.h.

6.13.2.12 int lspg_nextshot_struct::ay_isnull

Definition at line 339 of file pgpmac.h.

6.13.2.13 double lspg_nextshot_struct::az

alignment table z position

Definition at line 341 of file pgpmac.h.

6.13.2.14 double lspg_nextshot_struct::az2

next image alignment z position

Definition at line 392 of file pgpmac.h.

6.13.2.15 int lspg_nextshot_struct::az2_isnull

Definition at line 393 of file pgpmac.h.

6.13.2.16 int lspg_nextshot_struct::az_isnull

Definition at line 342 of file pgpmac.h.

6.13.2.17 pthread_cond_t lspg_nextshot_struct::cond

Condition to wait for a response from our postgresql server.

Definition at line 283 of file pgpmac.h.

6.13.2.18 double lspg_nextshot_struct::cx

centering table x position

Definition at line 329 of file pgpmac.h.

6.13.2.19 double lspg_nextshot_struct::cx2

next image centering table x position

Definition at line 380 of file pgpmac.h.

6.13.2.20 int lspg_nextshot_struct::cx2_isnull

Definition at line 381 of file pgpmac.h.

6.13.2.21 int lspg_nextshot_struct::cx_isnull

Definition at line 330 of file pgpmac.h.

6.13.2.22 double lspg_nextshot_struct::cy

centering table y position

Definition at line 332 of file pgpmac.h.

6.13.2.23 double lspg_nextshot_struct::cy2

next image centering table y position

Definition at line 383 of file pgpmac.h.

6.13.2.24 int lspg_nextshot_struct::cy2_isnull

Definition at line 384 of file pgpmac.h.

6.13.2.25 int lspg_nextshot_struct::cy_isnull

Definition at line 333 of file pgpmac.h.

6.13.2.26 char* lspg_nextshot_struct::dsdir

Directory for data relative to the ESAF home directory.

Definition at line 287 of file pgpmac.h.

6.13.2.27 int lspg_nextshot_struct::dsdir_isnull

Definition at line 288 of file pgpmac.h.

6.13.2.28 double lspg_nextshot_struct::dsdist

dataset defined detector distance

Definition at line 320 of file pgpmac.h.

6.13.2.29 double lspg_nextshot_struct::dsdist2

next image distance

Definition at line 374 of file pgpmac.h.

6.13.2.30 int lspg_nextshot_struct::dsdist2_isnull

Definition at line 375 of file pgpmac.h.

6.13.2.31 int lspg_nextshot_struct::dsdist_isnull

Definition at line 321 of file pgpmac.h.

6.13.2.32 double lspg_nextshot_struct::dsexp

dataset defined exposure time

Definition at line 299 of file pgpmac.h.

6.13.2.33 double lspg_nextshot_struct::dsexp2

next image exposure time

Definition at line 359 of file pgpmac.h.

6.13.2.34 int lspg_nextshot_struct::dsexp2_isnull

Definition at line 360 of file pgpmac.h.

6.13.2.35 int lspg_nextshot_struct::dsexp_isnull

Definition at line 300 of file pgpmac.h.

6.13.2.36 unsigned int lspg_nextshot_struct::dshpid

sample holder ID

Definition at line 326 of file pgpmac.h.

6.13.2.37 int lspg_nextshot_struct::dshpid_isnull

Definition at line 327 of file pgpmac.h.

6.13.2.38 double lspg_nextshot_struct::dskappa

dataset defined starting kappa angle

Definition at line 317 of file pgpmac.h.

6.13.2.39 double lspg_nextshot_struct::dskappa2

next image kappa position

Definition at line 371 of file pgpmac.h.

6.13.2.40 int lspg_nextshot_struct::dskappa2_isnull

Definition at line 372 of file pgpmac.h.

6.13.2.41 int lspg_nextshot_struct::dskappa_isnull

Definition at line 318 of file pgpmac.h.

6.13.2.42 double lspg_nextshot_struct::dsnrg

dataset defined energy

Definition at line 323 of file pgpmac.h.

6.13.2.43 double lspg_nextshot_struct::dsnrg2

next image energy

Definition at line 377 of file pgpmac.h.

6.13.2.44 int lspg_nextshot_struct::dsnrg2_isnull

Definition at line 378 of file pgpmac.h.

6.13.2.45 int lspg_nextshot_struct::dsnrg_isnull

Definition at line 324 of file pgpmac.h.

6.13.2.46 double lspg_nextshot_struct::dsomega

dataset defined starting omega angle

Definition at line 314 of file pgpmac.h.

6.13.2.47 double lspg_nextshot_struct::dsomega2

next image omega position

Definition at line 368 of file pgpmac.h.

6.13.2.48 int lspg_nextshot_struct::dsomega2_isnull

Definition at line 369 of file pgpmac.h.

6.13.2.49 int lspg_nextshot_struct::dsomega_isnull

Definition at line 315 of file pgpmac.h.

6.13.2.50 char* lspg_nextshot_struct::dsoscaxis

dataset defined oscillation axis (always omega)

Definition at line 296 of file pgpmac.h.

6.13.2.51 char* lspg_nextshot_struct::dsoscaxis2

next image ascillation axis (always "omega")

Definition at line 356 of file pgpmac.h.

6.13.2.52 int lspg_nextshot_struct::dsoscaxis2_isnull

Definition at line 357 of file pgpmac.h.

6.13.2.53 int lspg_nextshot_struct::dsoscaxis_isnull

Definition at line 297 of file pgpmac.h.

6.13.2.54 double lspg_nextshot_struct::dsowidth

dataset defined oscillation width

Definition at line 293 of file pgpmac.h.

6.13.2.55 double lspg_nextshot_struct::dsowidth2

next image oscillation width

Definition at line 353 of file pgpmac.h.

6.13.2.56 int lspg_nextshot_struct::dsowidth2_isnull

Definition at line 354 of file pgpmac.h.

6.13.2.57 int lspg_nextshot_struct::dsowidth_isnull

Definition at line 294 of file pgpmac.h.

6.13.2.58 double lspg_nextshot_struct::dsphi

dataset defined starting phi angle

Definition at line 311 of file pgpmac.h.

6.13.2.59 double lspg_nextshot_struct::dsphi2

next image phi position

Definition at line 365 of file pgpmac.h.

6.13.2.60 `int lspg_nextshot_struct::dsphi2_isnull`

Definition at line 366 of file pgpmac.h.

6.13.2.61 `int lspg_nextshot_struct::dsphi_isnull`

Definition at line 312 of file pgpmac.h.

6.13.2.62 `char* lspg_nextshot_struct::dspid`

ID string identifying this dataset.

Definition at line 290 of file pgpmac.h.

6.13.2.63 `int lspg_nextshot_struct::dspid_isnull`

Definition at line 291 of file pgpmac.h.

6.13.2.64 `pthread_mutex_t lspg_nextshot_struct::mutex`

Our mutex for sanity in the multi-threaded program.

Definition at line 282 of file pgpmac.h.

6.13.2.65 `int lspg_nextshot_struct::new_value_ready`

Our flag for the condition to wait for.

Definition at line 284 of file pgpmac.h.

6.13.2.66 `int lspg_nextshot_struct::no_rows_returned`

flag indicating that no rows were returned.

Definition at line 285 of file pgpmac.h.

6.13.2.67 `char* lspg_nextshot_struct::sfn`

file name

Definition at line 308 of file pgpmac.h.

6.13.2.68 `int lspg_nextshot_struct::sfn_isnull`

Definition at line 309 of file pgpmac.h.

6.13.2.69 `int lspg_nextshot_struct::sindex`

index of frame (used to generate the file extension)

Definition at line 347 of file pgpmac.h.

6.13.2.70 int lspg_nextshot_struct::sindex2

next image index number

Definition at line 398 of file pgpmac.h.

6.13.2.71 int lspg_nextshot_struct::sindex2_isnull

Definition at line 399 of file pgpmac.h.

6.13.2.72 int lspg_nextshot_struct::sindex_isnull

Definition at line 348 of file pgpmac.h.

6.13.2.73 long long lspg_nextshot_struct::skey

key identifying a particular image

Definition at line 302 of file pgpmac.h.

6.13.2.74 int lspg_nextshot_struct::skey_isnull

Definition at line 303 of file pgpmac.h.

6.13.2.75 double lspg_nextshot_struct::sstart

starting angle

Definition at line 305 of file pgpmac.h.

6.13.2.76 double lspg_nextshot_struct::sstart2

next image start angle

Definition at line 362 of file pgpmac.h.

6.13.2.77 int lspg_nextshot_struct::sstart2_isnull

Definition at line 363 of file pgpmac.h.

6.13.2.78 int lspg_nextshot_struct::sstart_isnull

Definition at line 306 of file pgpmac.h.

6.13.2.79 char* lspg_nextshot_struct::stype

"Normal" or "Gridsearch"

Definition at line 350 of file pgpmac.h.

6.13.2.80 char* lspg_nextshot_struct::stype2

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

Definition at line 401 of file pgpmac.h.

6.13.2.81 int lspg_nextshot_struct::stype2_isnull

Definition at line 402 of file pgpmac.h.

6.13.2.82 int lspg_nextshot_struct::stype_isnull

Definition at line 351 of file pgpmac.h.

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

- [pgpmac.h](#)

6.14 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](#)

6.14.1 Detailed Description

Data collection running object.

Definition at line 1131 of file lspg.c.

6.14.2 Field Documentation

6.14.2.1 pthread_cond_t lspg_seq_run_prep_struct::cond

Definition at line 1133 of file lspg.c.

6.14.2.2 pthread_mutex_t lspg_seq_run_prep_struct::mutex

Definition at line 1132 of file lspg.c.

6.14.2.3 int lspg_seq_run_prep_struct::new_value_ready

Definition at line 1134 of file lspg.c.

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

- [lspg.c](#)

6.15 lspg_starttransfer_struct Struct Reference

returns 1 if transfer can continue 0 to abort

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

Data Fields

- pthread_mutex_t [mutex](#)
Our mutex.
- pthread_cond_t [cond](#)
Our condition.
- int [new_value_ready](#)
flag for our condition
- int [no_rows_returned](#)
just in case, though this query should always return an integer, perhaps 0
- unsigned int [starttransfer](#)
sample number (4 8-bit segments: station, dewar (lid), puck, and position in the puck)

6.15.1 Detailed Description

returns 1 if transfer can continue 0 to abort

Definition at line 247 of file pgpmac.h.

6.15.2 Field Documentation

6.15.2.1 pthread_cond_t lspg_starttransfer_struct::cond

Our condition.

Definition at line 249 of file pgpmac.h.

6.15.2.2 pthread_mutex_t lspg_starttransfer_struct::mutex

Our mutex.

Definition at line 248 of file pgpmac.h.

6.15.2.3 int lspg_starttransfer_struct::new_value_ready

flag for our condition

Definition at line 250 of file pgpmac.h.

6.15.2.4 int lspg_starttransfer_struct::no_rows_returned

just in case, though this query should always return an integer, perhaps 0

Definition at line 251 of file pgpmac.h.

6.15.2.5 unsigned int lspg_starttransfer_struct::starttransfer

sample number (4 8-bit segments: station, dewar (lid), puck, and position in the puck)

Definition at line 253 of file pgpmac.h.

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

- [pgpmac.h](#)

6.16 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](#)

6.16.1 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 949 of file lspg.c.

6.16.2 Field Documentation

6.16.2.1 pthread_cond_t lspg_wait_for_detector_struct::cond

Definition at line 951 of file lspg.c.

6.16.2.2 pthread_mutex_t lspg_wait_for_detector_struct::mutex

Definition at line 950 of file lspg.c.

6.16.2.3 int lspg_wait_for_detector_struct::new_value_ready

Definition at line 952 of file lspg.c.

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

- [lspg.c](#)

6.17 lspg_waitcryo_struct Struct Reference

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

Data Fields

- pthread_mutex_t [mutex](#)

practice safe threading

- pthread_cond_t [cond](#)

for signaling

- int [new_value_ready](#)

OK, there is never a value, we need a variable for the conditional wait and this is what we call it everywhere else.

6.17.1 Detailed Description

Definition at line 180 of file pgpmac.h.

6.17.2 Field Documentation

6.17.2.1 pthread_cond_t lspg_waitcryo_struct::cond

for signaling

Definition at line 182 of file pgpmac.h.

6.17.2.2 pthread_mutex_t lspg_waitcryo_struct::mutex

practice safe threading

Definition at line 181 of file pgpmac.h.

6.17.2.3 int lspg_waitcryo_struct::new_value_ready

OK, there is never a value, we need a variable for the conditional wait and this is what we call it everywhere else.

Definition at line 183 of file pgpmac.h.

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

- [pgpmac.h](#)

6.18 lspgQueryQueueStruct Struct Reference

Store each query along with it's callback function.

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

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.

6.18.1 Detailed Description

Store each query along with it's callback function.

All calls are asynchronous

Definition at line 175 of file pgpmac.h.

6.18.2 Field Documentation

6.18.2.1 void(* lspgQueryQueueStruct::onResponse)(struct lspgQueryQueueStruct *qq, PResult *pgr)

Callback function for when a query returns a result.

Definition at line 177 of file pgpmac.h.

6.18.2.2 char lspgQueryQueueStruct::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

Definition at line 176 of file pgpmac.h.

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

- [pgpmac.h](#)

6.19 lspmac_ascii_buffers_struct Struct Reference

Data Fields

- uint16_t [command_buf](#)
- uint16_t [command_buf_cc](#)
- char [command_str](#) [160]
- uint16_t [response_buf](#)
- uint16_t [response_n](#)
- char [response_str](#) [256]

6.19.1 Detailed Description

Definition at line 354 of file lspmac.c.

6.19.2 Field Documentation

6.19.2.1 uint16_t lspmac_ascii_buffers_struct::command_buf

Definition at line 356 of file lspmac.c.

6.19.2.2 uint16_t lspmac_ascii_buffers_struct::command_buf_cc

Definition at line 357 of file lspmac.c.

6.19.2.3 `char lspmasciibuffers_struct::command_str[160]`

Definition at line 358 of file `lspmasc.c`.

6.19.2.4 `uint16_t lspmasciibuffers_struct::response_buf`

Definition at line 359 of file `lspmasc.c`.

6.19.2.5 `uint16_t lspmasciibuffers_struct::response_n`

Definition at line 360 of file `lspmasc.c`.

6.19.2.6 `char lspmasciibuffers_struct::response_str[256]`

Definition at line 361 of file `lspmasc.c`.

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

- [lspmasc.c](#)

6.20 `lspmascbi_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 position`
the current value.
- `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.

6.20.1 Detailed Description

Storage for binary inputs.

Definition at line 160 of file `pgpmac.h`.

6.20.2 Field Documentation

6.20.2.1 `char* Ispmac_bi_struct::changeEventOff`

Event to send when the value changes to 0.

Definition at line 168 of file `pgpmac.h`.

6.20.2.2 `char* Ispmac_bi_struct::changeEventOn`

Event to send when the value changes to 1.

Definition at line 167 of file `pgpmac.h`.

6.20.2.3 `int Ispmac_bi_struct::first_time`

flag indicating we've not read the input even once

Definition at line 166 of file `pgpmac.h`.

6.20.2.4 `int Ispmac_bi_struct::mask`

mask for the bit in the status register

Definition at line 163 of file `pgpmac.h`.

6.20.2.5 `pthread_mutex_t Ispmac_bi_struct::mutex`

so we don't get confused

Definition at line 162 of file `pgpmac.h`.

6.20.2.6 `int Ispmac_bi_struct::position`

the current value.

Definition at line 164 of file `pgpmac.h`.

6.20.2.7 `int Ispmac_bi_struct::previous`

the previous value

Definition at line 165 of file `pgpmac.h`.

6.20.2.8 `int* Ispmac_bi_struct::ptr`

points to the location in the status buffer

Definition at line 161 of file `pgpmac.h`.

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

- [pgpmac.h](#)

6.21 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
- [char * event](#)
event name to send
- [void\(* onResponse\)\(struct lspmac_cmd_queue_struct *, int, char *\)](#)
function to call when response is received. args are (int fd, nreturned, buffer)

6.21.1 Detailed Description

PMAC command queue item.

Command queue items are fixed length to simplify memory management.

Definition at line 86 of file pgpmac.h.

6.21.2 Field Documentation

6.21.2.1 [char* lspmac_cmd_queue_struct::event](#)

event name to send

Definition at line 90 of file pgpmac.h.

6.21.2.2 [int lspmac_cmd_queue_struct::no_reply](#)

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

Definition at line 88 of file pgpmac.h.

6.21.2.3 [void\(* lspmac_cmd_queue_struct::onResponse\)\(struct lspmac_cmd_queue_struct *, int, char *\)](#)

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

Definition at line 91 of file pgpmac.h.

6.21.2.4 [pmac_cmd_t lspmac_cmd_queue_struct::pcmd](#)

the pmac command to send

Definition at line 87 of file pgpmac.h.

6.21.2.5 `struct timespec lspmac_cmd_queue_struct::time_sent`

time this item was dequeued and sent to the pmac

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

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

- [pgpmac.h](#)

6.22 `lspmac_combined_move_struct` Struct Reference

Data Fields

- int [Delta](#)
- int [moveme](#)
- int [coord_num](#)
- int [axis](#)

6.22.1 Detailed Description

Definition at line 377 of file `lspmac.c`.

6.22.2 Field Documentation

6.22.2.1 `int lspmac_combined_move_struct::axis`

Definition at line 381 of file `lspmac.c`.

6.22.2.2 `int lspmac_combined_move_struct::coord_num`

Definition at line 380 of file `lspmac.c`.

6.22.2.3 `int lspmac_combined_move_struct::Delta`

Definition at line 378 of file `lspmac.c`.

6.22.2.4 `int lspmac_combined_move_struct::moveme`

Definition at line 379 of file `lspmac.c`.

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

- [lspmac.c](#)

6.23 `lspmac_dpascii_queue_struct` Struct Reference

Data Fields

- char * [event](#)
- char [pl](#) [160]

6.23.1 Detailed Description

Definition at line 368 of file lspmac.c.

6.23.2 Field Documentation

6.23.2.1 char* lspmac_dpascii_queue_struct::event

Definition at line 369 of file lspmac.c.

6.23.2.2 char lspmac_dpascii_queue_struct::pl[160]

Definition at line 370 of file lspmac.c.

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

- [lspmac.c](#)

6.24 lspmac_motor_struct Struct Reference

Motor information.

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

Data Fields

- int [magic](#)
magic number identifying this as a motor structure
- 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 [command_sent](#)
Motion command verified sent to pmac.
- int [motion_seen](#)
set to 1 when motion has been verified to have started
- [pmac_cmd_queue_t](#) * [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_pg_position](#)
previous position reported to postgresql
- double [reported_position](#)
previous position reported to redis
- 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 * [dac_mvar](#)
controlling mvariable as a string
- char * [name](#)
Name of motor as referred by ls database kvs table.
- [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](#) * [axis](#)
the axis (X, Y, Z, etc) or null if not in a coordinate system
- [lsredis_obj_t](#) * [coord_num](#)
coordinate system this motor belongs to (0 if none)
- [lsredis_obj_t](#) * [home](#)
pmac commands to home motor
- [lsredis_obj_t](#) * [inactive_init](#)
pmac commands to inactivate the motor
- [lsredis_obj_t](#) * [in_position_band](#)
moves within this amount are ignored UNITS ARE 1/16 COUNT
- [lsredis_obj_t](#) * [max_accel](#)
our maximum acceleration (cts/msec²)
- [lsredis_obj_t](#) * [max_pos](#)
our maximum position (soft limit)
- [lsredis_obj_t](#) * [max_speed](#)
our maximum speed (cts/msec)
- [lsredis_obj_t](#) * [min_pos](#)
our minimum position (soft limit)
- [lsredis_obj_t](#) * [motor_num](#)
pmac motor number
- [lsredis_obj_t](#) * [neutral_pos](#)
zero offset
- [lsredis_obj_t](#) * [pos_limit_hit](#)
positive limit status
- [lsredis_obj_t](#) * [neg_limit_hit](#)
negative limit status
- [lsredis_obj_t](#) * [precision](#)
moves of less than this amount may be ignored

- `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 * redis_position`
how we report our position to the world
- `lsredis_obj_t * status_str`
A talky version of the status.
- `lsredis_obj_t * u2c`
conversion from counts to units: 0.0 means not loaded yet
- `lsredis_obj_t * unit`
string to use as the units
- `lsredis_obj_t * update_resolution`
Change needs to be at least this big to report as a new position to the database.
- `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.
- `int(* moveAbs)(struct lspmac_motor_struct *, double)`
function to move the motor
- `int(* jogAbs)(struct lspmac_motor_struct *, double)`
function to move the motor
- `double * lut`
lookup table (instead of u2c)
- `int nlut`
length of lut
- `WINDOW * win`
our ncurses window

6.24.1 Detailed Description

Motor information.

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

Definition at line 101 of file pgpmac.h.

6.24.2 Field Documentation

6.24.2.1 `lsredis_obj_t* lspmac_motor_struct::active`

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

Definition at line 124 of file pgpmac.h.

6.24.2.2 `lsredis_obj_t* lspmac_motor_struct::active_init`

pmac commands to make this motor active

Definition at line 125 of file pgpmac.h.

6.24.2.3 `int lspmac_motor_struct::actual_pos_cnts`

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

Definition at line 113 of file `pgpmac.h`.

6.24.2.4 `int* lspmac_motor_struct::actual_pos_cnts_p`

pointer to the `md2_status` structure to the actual position

Definition at line 112 of file `pgpmac.h`.

6.24.2.5 `lsredis_obj_t* lspmac_motor_struct::axis`

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

Definition at line 126 of file `pgpmac.h`.

6.24.2.6 `int lspmac_motor_struct::command_sent`

Motion command verified sent to pmac.

Definition at line 107 of file `pgpmac.h`.

6.24.2.7 `pthread_cond_t lspmac_motor_struct::cond`

used to signal when a motor is done moving

Definition at line 104 of file `pgpmac.h`.

6.24.2.8 `lsredis_obj_t* lspmac_motor_struct::coord_num`

coordinate system this motor belongs to (0 if none)

Definition at line 127 of file `pgpmac.h`.

6.24.2.9 `char* lspmac_motor_struct::dac_mvar`

controlling mvariable as a string

Definition at line 122 of file `pgpmac.h`.

6.24.2.10 `lsredis_obj_t* lspmac_motor_struct::home`

pmac commands to home motor

Definition at line 128 of file `pgpmac.h`.

6.24.2.11 `int lspmac_motor_struct::homing`

Homing routine started.

Definition at line 110 of file `pgpmac.h`.

6.24.2.12 `Isredis_obj_t* lspmac_motor_struct::in_position_band`

moves within this amount are ignored UNITS ARE 1/16 COUNT

Definition at line 130 of file pgpmac.h.

6.24.2.13 `Isredis_obj_t* lspmac_motor_struct::inactive_init`

pmac commands to inactivate the motor

Definition at line 129 of file pgpmac.h.

6.24.2.14 `int(* lspmac_motor_struct::jogAbs)(struct lspmac_motor_struct *, double)`

function to move the motor

Definition at line 151 of file pgpmac.h.

6.24.2.15 `double* lspmac_motor_struct::lut`

lookup table (instead of u2c)

Definition at line 152 of file pgpmac.h.

6.24.2.16 `int lspmac_motor_struct::magic`

magic number identifying this as a motor structure

Definition at line 102 of file pgpmac.h.

6.24.2.17 `Isredis_obj_t* lspmac_motor_struct::max_accel`

our maximum acceleration (cts/msec²)

Definition at line 131 of file pgpmac.h.

6.24.2.18 `Isredis_obj_t* lspmac_motor_struct::max_pos`

our maximum position (soft limit)

Definition at line 132 of file pgpmac.h.

6.24.2.19 `Isredis_obj_t* lspmac_motor_struct::max_speed`

our maximum speed (cts/msec)

Definition at line 133 of file pgpmac.h.

6.24.2.20 `Isredis_obj_t* lspmac_motor_struct::min_pos`

our minimum position (soft limit)

Definition at line 134 of file pgpmac.h.

6.24.2.21 int lspmac_motor_struct::motion_seen

set to 1 when motion has been verified to have started

Definition at line 108 of file pgpmac.h.

6.24.2.22 lsredis_obj_t* lspmac_motor_struct::motor_num

pmac motor number

Definition at line 135 of file pgpmac.h.

6.24.2.23 int(* lspmac_motor_struct::moveAbs)(struct lspmac_motor_struct *, double)

function to move the motor

Definition at line 150 of file pgpmac.h.

6.24.2.24 pthread_mutex_t lspmac_motor_struct::mutex

coordinate waiting for motor to be done

Definition at line 103 of file pgpmac.h.

6.24.2.25 char* lspmac_motor_struct::name

Name of motor as referred by ls database kvs table.

Definition at line 123 of file pgpmac.h.

6.24.2.26 lsredis_obj_t* lspmac_motor_struct::neg_limit_hit

negative limit status

Definition at line 138 of file pgpmac.h.

6.24.2.27 lsredis_obj_t* lspmac_motor_struct::neutral_pos

zero offset

Definition at line 136 of file pgpmac.h.

6.24.2.28 int lspmac_motor_struct::nlut

length of lut

Definition at line 153 of file pgpmac.h.

6.24.2.29 int lspmac_motor_struct::not_done

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

Definition at line 105 of file pgpmac.h.

6.24.2.30 `lsredis_obj_t* lspmac_motor_struct::pos_limit_hit`

positive limit status

Definition at line 137 of file pgpmac.h.

6.24.2.31 `double lspmac_motor_struct::position`

scaled position

Definition at line 114 of file pgpmac.h.

6.24.2.32 `pmac_cmd_queue_t* lspmac_motor_struct::pq`

the queue item requesting motion. Used to check time request was made

Definition at line 109 of file pgpmac.h.

6.24.2.33 `lsredis_obj_t* lspmac_motor_struct::precision`

moves of less than this amount may be ignored

Definition at line 139 of file pgpmac.h.

6.24.2.34 `lsredis_obj_t* lspmac_motor_struct::printf_fmt`

printf format

Definition at line 140 of file pgpmac.h.

6.24.2.35 `void(* lspmac_motor_struct::read)(struct lspmac_motor_struct *)`

method to read the motor status and position

Definition at line 106 of file pgpmac.h.

6.24.2.36 `int lspmac_motor_struct::read_mask`

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

Definition at line 149 of file pgpmac.h.

6.24.2.37 `int* lspmac_motor_struct::read_ptr`

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

Definition at line 148 of file pgpmac.h.

6.24.2.38 `lsredis_obj_t* lspmac_motor_struct::redis_fmt`

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

Definition at line 141 of file pgpmac.h.

6.24.2.39 `lsredis_obj_t* lspmac_motor_struct::redis_position`

how we report our position to the world

Definition at line 142 of file pgpmac.h.

6.24.2.40 `double lspmac_motor_struct::reported_pg_position`

previous position reported to postgresql

Definition at line 115 of file pgpmac.h.

6.24.2.41 `double lspmac_motor_struct::reported_position`

previous position reported to redis

Definition at line 116 of file pgpmac.h.

6.24.2.42 `int lspmac_motor_struct::requested_pos_cnts`

requested position

Definition at line 111 of file pgpmac.h.

6.24.2.43 `double lspmac_motor_struct::requested_position`

The position as requested by the user.

Definition at line 117 of file pgpmac.h.

6.24.2.44 `int lspmac_motor_struct::status1`

local copy of status1

Definition at line 119 of file pgpmac.h.

6.24.2.45 `int* lspmac_motor_struct::status1_p`

First 24 bit PMAC motor status word.

Definition at line 118 of file pgpmac.h.

6.24.2.46 `int lspmac_motor_struct::status2`

local copy of status2

Definition at line 121 of file pgpmac.h.

6.24.2.47 `int* lspmac_motor_struct::status2_p`

Second 24 bit PMAC motor status word.

Definition at line 120 of file pgpmac.h.

6.24.2.48 `Isredis_obj_t* lspmac_motor_struct::status_str`

A talky version of the status.

Definition at line 143 of file `pgpmac.h`.

6.24.2.49 `Isredis_obj_t* lspmac_motor_struct::u2c`

conversion from counts to units: 0.0 means not loaded yet

Definition at line 144 of file `pgpmac.h`.

6.24.2.50 `Isredis_obj_t* lspmac_motor_struct::unit`

string to use as the units

Definition at line 145 of file `pgpmac.h`.

6.24.2.51 `Isredis_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 146 of file `pgpmac.h`.

6.24.2.52 `WINDOW* lspmac_motor_struct::win`

our ncurses window

Definition at line 154 of file `pgpmac.h`.

6.24.2.53 `char* lspmac_motor_struct::write_fmt`

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

Definition at line 147 of file `pgpmac.h`.

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

- [pgpmac.h](#)

6.25 `Isredis_obj_struct` Struct Reference

Redis Object Basic object whose value is sychronized 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*

6.25.1 Detailed Description

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

Definition at line 38 of file pgpmac.h.

6.25.2 Field Documentation

6.25.2.1 char** Isredis_obj_struct::avalue

our value as an array of strings

Definition at line 50 of file pgpmac.h.

6.25.2.2 int Isredis_obj_struct::bvalue

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

Definition at line 51 of file pgpmac.h.

6.25.2.3 pthread_cond_t Isredis_obj_struct::cond

wait for a valid value

Definition at line 40 of file pgpmac.h.

6.25.2.4 char Isredis_obj_struct::cvalue

just the first character of our value

Definition at line 52 of file pgpmac.h.

6.25.2.5 double lsredis_obj_struct::dvalue

our value as a double

Definition at line 48 of file pgpmac.h.

6.25.2.6 char* lsredis_obj_struct::events_name

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

Definition at line 45 of file pgpmac.h.

6.25.2.7 int lsredis_obj_struct::hits

number of times we've searched for this key

Definition at line 53 of file pgpmac.h.

6.25.2.8 char* lsredis_obj_struct::key

The redis key for this object.

Definition at line 44 of file pgpmac.h.

6.25.2.9 long int lsredis_obj_struct::lvalue

our value as a long

Definition at line 49 of file pgpmac.h.

6.25.2.10 pthread_mutex_t lsredis_obj_struct::mutex

Don't let anyone use an old value.

Definition at line 39 of file pgpmac.h.

6.25.2.11 struct lsredis_obj_struct* lsredis_obj_struct::next

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

Definition at line 41 of file pgpmac.h.

6.25.2.12 char lsredis_obj_struct::valid

1 if we think the value is good, 0 otherwise

Definition at line 42 of file pgpmac.h.

6.25.2.13 char* lsredis_obj_struct::value

our value

Definition at line 47 of file pgpmac.h.

6.25.2.14 int lsredis_obj_struct::value_length

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

Definition at line 46 of file pgpmac.h.

6.25.2.15 int lsredis_obj_struct::wait_for_me

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

Definition at line 43 of file pgpmac.h.

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

- [pgpmac.h](#)

6.26 lsredis_preset_list_struct Struct Reference

Data Fields

- struct [lsredis_preset_list_struct](#) * [next](#)
- char * [key](#)
- int [index](#)
- [lsredis_obj_t](#) * [name](#)
- [lsredis_obj_t](#) * [position](#)

6.26.1 Detailed Description

Definition at line 94 of file lsredis.c.

6.26.2 Field Documentation

6.26.2.1 int lsredis_preset_list_struct::index

Definition at line 97 of file lsredis.c.

6.26.2.2 char* lsredis_preset_list_struct::key

Definition at line 96 of file lsredis.c.

6.26.2.3 lsredis_obj_t* lsredis_preset_list_struct::name

Definition at line 98 of file lsredis.c.

6.26.2.4 struct lsredis_preset_list_struct* lsredis_preset_list_struct::next

Definition at line 95 of file lsredis.c.

6.26.2.5 `lsredis_obj_t*` `lsredis_preset_list_struct::position`

Definition at line 99 of file `lsredis.c`.

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

- [lsredis.c](#)

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

6.27.1 Detailed Description

Everything we need to know about a timer.

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

6.27.2 Field Documentation

6.27.2.1 `long int` `lstimer_list_struct::delay_nsecs`

nano seconds of delay

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

6.27.2.2 `long int ltimer_list_struct::delay_secs`

number of seconds for a periodic delay

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

6.27.2.3 `char ltimer_list_struct::event[LSEVENTS_EVENT_LENGTH]`

the event to send

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

6.27.2.4 `long int ltimer_list_struct::init_nsecs`

our initialization time

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

6.27.2.5 `long int ltimer_list_struct::init_secs`

our initialization time

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

6.27.2.6 `long int ltimer_list_struct::last_nsecs`

the last time this timer was triggered

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

6.27.2.7 `long int ltimer_list_struct::last_secs`

the last time this timer was triggered

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

6.27.2.8 `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`.

6.27.2.9 `long int ltimer_list_struct::next_nsecs`

nano seconds of next alarm

Definition at line 27 of file `ltimer.c`.

6.27.2.10 `long int ltimer_list_struct::next_secs`

epoch (seconds) of next alarm

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

6.27.2.11 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](#)

6.28 md2cmds_cmd_kv_struct Struct Reference

Data Fields

- char * [k](#)
- int(* [v](#))(const char *)

6.28.1 Detailed Description

Definition at line 39 of file md2cmds.c.

6.28.2 Field Documentation

6.28.2.1 char* md2cmds_cmd_kv_struct::k

Definition at line 40 of file md2cmds.c.

6.28.2.2 int(* md2cmds_cmd_kv_struct::v)(const char *)

Definition at line 41 of file md2cmds.c.

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

- [md2cmds.c](#)

6.29 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](#)

6.29.1 Detailed Description

The block of memory retrieved in a status request.

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

6.29.2 Field Documentation

6.29.2.1 int `md2StatusStruct::acc11c_1`

Definition at line 322 of file `lspmac.c`.

6.29.2.2 int `md2StatusStruct::acc11c_2`

Definition at line 323 of file `lspmac.c`.

6.29.2.3 int `md2StatusStruct::acc11c_3`

Definition at line 324 of file `lspmac.c`.

6.29.2.4 int `md2StatusStruct::acc11c_5`

Definition at line 325 of file `lspmac.c`.

6.29.2.5 int `md2StatusStruct::acc11c_6`

Definition at line 326 of file `lspmac.c`.

6.29.2.6 int `md2StatusStruct::alignx_act_pos`

Definition at line 306 of file `lspmac.c`.

6.29.2.7 int `md2StatusStruct::alignx_status_1`

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

6.29.2.8 int `md2StatusStruct::alignx_status_2`

Definition at line 289 of file `lspmac.c`.

6.29.2.9 int `md2StatusStruct::aligny_act_pos`

Definition at line 307 of file `lspmac.c`.

6.29.2.10 int md2StatusStruct::aligny_status_1

Definition at line 273 of file lspmacc.c.

6.29.2.11 int md2StatusStruct::aligny_status_2

Definition at line 290 of file lspmacc.c.

6.29.2.12 int md2StatusStruct::alignz_act_pos

Definition at line 308 of file lspmacc.c.

6.29.2.13 int md2StatusStruct::alignz_status_1

Definition at line 274 of file lspmacc.c.

6.29.2.14 int md2StatusStruct::alignz_status_2

Definition at line 291 of file lspmacc.c.

6.29.2.15 int md2StatusStruct::analyzer_act_pos

Definition at line 309 of file lspmacc.c.

6.29.2.16 int md2StatusStruct::analyzer_status_1

Definition at line 275 of file lspmacc.c.

6.29.2.17 int md2StatusStruct::analyzer_status_2

Definition at line 292 of file lspmacc.c.

6.29.2.18 int md2StatusStruct::aperturey_act_pos

Definition at line 311 of file lspmacc.c.

6.29.2.19 int md2StatusStruct::aperturey_status_1

Definition at line 277 of file lspmacc.c.

6.29.2.20 int md2StatusStruct::aperturey_status_2

Definition at line 294 of file lspmacc.c.

6.29.2.21 int md2StatusStruct::aperturez_act_pos

Definition at line 312 of file lspmacc.c.

6.29.2.22 int md2StatusStruct::aperturez_status_1

Definition at line 278 of file lspmac.c.

6.29.2.23 int md2StatusStruct::aperturez_status_2

Definition at line 295 of file lspmac.c.

6.29.2.24 int md2StatusStruct::back_dac

Definition at line 328 of file lspmac.c.

6.29.2.25 int md2StatusStruct::capy_act_pos

Definition at line 313 of file lspmac.c.

6.29.2.26 int md2StatusStruct::capy_status_1

Definition at line 279 of file lspmac.c.

6.29.2.27 int md2StatusStruct::capy_status_2

Definition at line 296 of file lspmac.c.

6.29.2.28 int md2StatusStruct::capz_act_pos

Definition at line 314 of file lspmac.c.

6.29.2.29 int md2StatusStruct::capz_status_1

Definition at line 280 of file lspmac.c.

6.29.2.30 int md2StatusStruct::capz_status_2

Definition at line 297 of file lspmac.c.

6.29.2.31 int md2StatusStruct::centerx_act_pos

Definition at line 316 of file lspmac.c.

6.29.2.32 int md2StatusStruct::centerx_status_1

Definition at line 282 of file lspmac.c.

6.29.2.33 int md2StatusStruct::centerx_status_2

Definition at line 299 of file lspmac.c.

6.29.2.34 int md2StatusStruct::centery_act_pos

Definition at line 317 of file lspmac.c.

6.29.2.35 int md2StatusStruct::centery_status_1

Definition at line 283 of file lspmac.c.

6.29.2.36 int md2StatusStruct::centery_status_2

Definition at line 300 of file lspmac.c.

6.29.2.37 int md2StatusStruct::dummy1

Definition at line 270 of file lspmac.c.

6.29.2.38 int md2StatusStruct::dummy2

Definition at line 287 of file lspmac.c.

6.29.2.39 int md2StatusStruct::dummy3

Definition at line 304 of file lspmac.c.

6.29.2.40 int md2StatusStruct::dummy4

Definition at line 331 of file lspmac.c.

6.29.2.41 int md2StatusStruct::dummy5

Definition at line 332 of file lspmac.c.

6.29.2.42 int md2StatusStruct::dummy6

Definition at line 333 of file lspmac.c.

6.29.2.43 int md2StatusStruct::dummy7

Definition at line 334 of file lspmac.c.

6.29.2.44 int md2StatusStruct::dummy8

Definition at line 335 of file lspmac.c.

6.29.2.45 int md2StatusStruct::dummy9

Definition at line 336 of file lspmac.c.

6.29.2.46 `int md2StatusStruct::dummyA`

Definition at line 337 of file `lspmac.c`.

6.29.2.47 `int md2StatusStruct::dummyB`

Definition at line 338 of file `lspmac.c`.

6.29.2.48 `int md2StatusStruct::front_dac`

Definition at line 327 of file `lspmac.c`.

6.29.2.49 `int md2StatusStruct::fs_has_opened`

Definition at line 342 of file `lspmac.c`.

6.29.2.50 `int md2StatusStruct::fs_has_opened_globally`

Definition at line 343 of file `lspmac.c`.

6.29.2.51 `int md2StatusStruct::fs_is_open`

Definition at line 340 of file `lspmac.c`.

6.29.2.52 `int md2StatusStruct::kappa_act_pos`

Definition at line 318 of file `lspmac.c`.

6.29.2.53 `int md2StatusStruct::kappa_status_1`

Definition at line 284 of file `lspmac.c`.

6.29.2.54 `int md2StatusStruct::kappa_status_2`

Definition at line 301 of file `lspmac.c`.

6.29.2.55 `int md2StatusStruct::moving_flags`

Definition at line 346 of file `lspmac.c`.

6.29.2.56 `int md2StatusStruct::number_passes`

Definition at line 344 of file `lspmac.c`.

6.29.2.57 `int md2StatusStruct::omega_act_pos`

Definition at line 305 of file `lspmac.c`.

6.29.2.58 int md2StatusStruct::omega_status_1

Definition at line 271 of file lspmac.c.

6.29.2.59 int md2StatusStruct::omega_status_2

Definition at line 288 of file lspmac.c.

6.29.2.60 int md2StatusStruct::phi_act_pos

Definition at line 319 of file lspmac.c.

6.29.2.61 int md2StatusStruct::phi_status_1

Definition at line 285 of file lspmac.c.

6.29.2.62 int md2StatusStruct::phi_status_2

Definition at line 302 of file lspmac.c.

6.29.2.63 int md2StatusStruct::phiscan

Definition at line 341 of file lspmac.c.

6.29.2.64 int md2StatusStruct::scint_act_pos

Definition at line 315 of file lspmac.c.

6.29.2.65 int md2StatusStruct::scint_piezo

Definition at line 329 of file lspmac.c.

6.29.2.66 int md2StatusStruct::scint_status_1

Definition at line 281 of file lspmac.c.

6.29.2.67 int md2StatusStruct::scint_status_2

Definition at line 298 of file lspmac.c.

6.29.2.68 int md2StatusStruct::zoom_act_pos

Definition at line 310 of file lspmac.c.

6.29.2.69 int md2StatusStruct::zoom_status_1

Definition at line 276 of file lspmac.c.

6.29.2.70 int md2StatusStruct::zoom_status_2

Definition at line 293 of file lspmac.c.

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

- [lspmac.c](#)

6.30 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.

6.30.1 Detailed Description

PMAC ethernet packet definition.

Taken directly from the Delta Tau documentation.

Definition at line 73 of file pgpmac.h.

6.30.2 Field Documentation

6.30.2.1 unsigned char tagEthernetCmd::bData[1492]

The data buffer, if required.

Definition at line 79 of file pgpmac.h.

6.30.2.2 unsigned char tagEthernetCmd::Request

The command to run (VR_PMAC_GETMEM, etc).

Definition at line 75 of file pgpmac.h.

6.30.2.3 unsigned char tagEthernetCmd::RequestType

VR_UPLOAD or VR_DOWNLOAD.

Definition at line 74 of file pgpmac.h.

6.30.2.4 unsigned short tagEthernetCmd::wIndex

Command parameter 2.

Definition at line 77 of file pgpmac.h.

6.30.2.5 unsigned short tagEthernetCmd::wLength

Number of bytes in bData.

Definition at line 78 of file pgpmac.h.

6.30.2.6 unsigned short tagEthernetCmd::wValue

Command parameter 1.

Definition at line 76 of file pgpmac.h.

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

- [pgpmac.h](#)

Chapter 7

File Documentation

7.1 iniParser.py File Reference

Data Structures

- class [iniParser.iniParser](#)

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Namespaces

- namespace [iniParser](#)

Variables

- tuple [iniParser.ip](#) `iniParser("21-ID-E/microdiff_hard.ini")`

7.2 lsevents.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.
- struct [lsevents_callbacks_struct](#)
lsevents linked list of callbacks for each event
- struct [lsevents_event_names_struct](#)
linked list of all the event names used to regenerate the hash table

Macros

- `#define LSEVENTS_QUEUE_LENGTH 512`

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.
- typedef struct
[lsevents_callbacks_struct](#) [lsevents_callbacks_t](#)
Lsevents linked list of callbacks for each event
- typedef struct
[lsevents_event_names_struct](#) [lsevents_event_names_t](#)
linked list of all the event names used to regenerate the hash table

Functions

- void [lsevents_send_event](#) (char *fmt,...)
Call the callback routines for the given event.
- void [lsevents_add_listener](#) (char *raw_regexp, 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.
- [lsevents_callbacks_t](#) * [lsevents_register_event](#) (char *event)
Add a new event name and find matching callbacks as a returned linked list.
- void [lsevents_preregister_event](#) (char *fmt,...)
- 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 int [lsevents_max_events](#) = 1024
- static int [lsevents_n_events](#) = 0
- static struct hsearch_data [lsevents_event_name_ht](#)
- static [lsevents_listener_t](#) * [lsevents_listeners_p](#) = NULL
Pointer to the first item in the link list of listeners.
- static [lsevents_event_names_t](#) * [lsevents_event_names](#) = NULL

- 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

7.2.1 Detailed Description

event subsystem for inter-pgpmac communication

Date

2012

Author

Keith Brister

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

7.2.2 Macro Definition Documentation

7.2.2.1 #define LSEVENTS_QUEUE_LENGTH 512

Definition at line 10 of file lsevents.c.

7.2.3 Typedef Documentation

7.2.3.1 typedef struct lsevents_callbacks_struct lsevents_callbacks_t

lsevents linked list of callbacks for each event

7.2.3.2 typedef struct lsevents_event_names_struct lsevents_event_names_t

linked list of all the event names used to regenerate the hash table

7.2.3.3 typedef struct lsevents_listener_struct lsevents_listener_t

Linked list of event listeners.

7.2.3.4 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.

7.2.4 Function Documentation

7.2.4.1 void lsevents_add_listener (char * raw_regexp, void (*)(char *) cb)

Add a callback routine to listen for a specific event.

Parameters

<i>raw_regexp</i>	String value of regular expression to listen to
<i>cb</i>	the routine to call

Definition at line 99 of file lsevents.c.

```

lsevents_listener_t    *new;
lsevents_event_names_t *enp;
lsevents_callbacks_t    *cbp;
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, raw_regexp, 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( raw_regexp);
new->cb = cb;

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

for( enp = lsevents_event_names; enp != NULL; enp = enp->
    next) {
    if( regexec( &new->re, enp->event, 0, NULL, 0) == 0) {
        cbp = calloc( 1, sizeof( lsevents_callbacks_t))
        ;
        cbp->cb = cb;
        cbp->next = enp->cbl;
        enp->cbl = cbp;
    }
}

pthread_mutex_unlock( &lsevents_listener_mutex);

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

```

7.2.4.2 void lsevents_init ()

Initialize this module.

Definition at line 373 of file lsevents.c.

```

    {
        pthread_mutexattr_t mutex_initializer;

        // Use recursive mutexs
        //
        pthread_mutexattr_init( &mutex_initializer);
        pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

        pthread_mutex_init( &lsevents_queue_mutex, &
            mutex_initializer);
        pthread_cond_init( &lsevents_queue_cond, NULL);
        pthread_mutex_init( &lsevents_listener_mutex, &
            mutex_initializer);

        hcreate_r( 2*lsevents_max_events, &lsevents_event_name_ht
            );
    }

```

7.2.4.3 void lsevents_preregister_event (char * fmt, ...)

Definition at line 314 of file lsevents.c.

```

    {
        char s[128];
        va_list arg_ptr;

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

        lsevents_register_event( s);
    }

```

7.2.4.4 lsevents_callbacks_t* lsevents_register_event (char * event)

Add a new event name and find matching callbacks as a returned linked list.

Definition at line 221 of file lsevents.c.

```

    {
        ENTRY entry_in, *entry_outp;
        int err;
        lsevents_callbacks_t *new_cb;
        lsevents_event_names_t *new_event_name, *enp;
        lsevents_listener_t *p;

        //
        // Search for event
        //
        entry_in.key = event;
        entry_in.data = NULL;

        pthread_mutex_lock( &lsevents_listener_mutex);
        err = hsearch_r( entry_in, FIND, &entry_outp, &lsevents_event_name_ht
            );
        if( err != 0) {
            //
            // Success, we found the entry
            //
            enp = entry_outp->data;
            pthread_mutex_unlock( &lsevents_listener_mutex);
            return enp->cbl;
        }

        if( errno != ESRCH) {
            //
            // Something awful happened. At least log it
            //
            lslogging_log_message( "lsevents_register_event:
                hsearch_r returned %d: %s", errno, strerror( errno));
            pthread_mutex_unlock( &lsevents_listener_mutex);
            return NULL;
        }

        lslogging_log_message( "lsevents_register_event: adding

```

```

        event '%s', event);
//
// Not Found
//
// Create new event name item
new_event_name = calloc( 1, sizeof( lsevents_event_names_t
));
new_event_name->event = strdup( event);
new_event_name->cbl = NULL;

//
// Find matching callbacks
//
for( p = lsevents_listeners_p; p != NULL; p = p->next
) {
    if( regexec( &p->re, event, 0, NULL, 0) == 0) {
        new_cb = calloc( 1, sizeof( lsevents_callbacks_t));
        new_cb->cb = p->cb;
        new_cb->next = new_event_name->cbl;
        new_event_name->cbl = new_cb;
    }
}

//
// Add the new event to our linked list
//
new_event_name->next = lsevents_event_names;
lsevents_event_names = new_event_name;

//
// Also add the new event to our hash table
//
entry_in.key = new_event_name->event;
entry_in.data = new_event_name;
err = hsearch_r( entry_in, ENTER, &entry_outp, &lsevents_event_name_ht
);
if( err == 0) {
    //
    // Something bad happend but we can still return a valid callback list. We
    // just can't use the hash table to find it again later
    //
    lslogging_log_message( "lsevents_register_event: Could
        not add event name: hsearch_r returned %d: %s", errno, strerror( errno));
    pthread_mutex_unlock( &lsevents_listener_mutex);
    return new_event_name->cbl;
}

if( ++lsevents_n_events >= lsevents_max_events
) {
    hdestroy_r( &lsevents_event_name_ht);
    lslogging_log_message( "lsevents_register_event:
        Increasing event name hash table to %d. lsevents_n_events=%d", 2 *
        lsevents_max_events, lsevents_n_events);
    lsevents_max_events *= 2;
    hcreate_r( lsevents_max_events * 2, &
        lsevents_event_name_ht);
    for( enp = lsevents_event_names; enp != NULL; enp = enp
        ->next) {
        entry_in.key = enp->event;
        entry_in.data = enp;
        hsearch_r( entry_in, ENTER, &entry_outp, &lsevents_event_name_ht
        );
    }
}
lslogging_log_message( "lsevents_register_event: added
    event '%s', event);
pthread_mutex_unlock( &lsevents_listener_mutex);
return new_event_name->cbl;
}

```

7.2.4.5 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 (possibly a regular expression string)
<i>cb</i>	The callback routine to remove

Definition at line 157 of file lsevents.c.


```

{

lsevents_listener_t *last, *current;
lsevents_event_names_t *enp;
lsevents_callbacks_t *cbp, *last_cbp;

//
// 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;
    }
    last = current;
}

if( current == NULL) {
    lslogging_log_message( "lsevents_remove_listener:
        Could not find this listener for event '%s'", event);
    pthread_mutex_unlock( &lsevents_listener_mutex);
    return;
}

//
// Remove callback from lists of event names
//
for( enp = lsevents_event_names; enp != NULL; enp = enp->
    next) {
    if( regexec( &current->re, enp->event, 0, NULL, 0) == 0) {
        last_cbp = NULL;
        for( cbp = enp->cb1; cbp != NULL; cbp = cbp->next) {
            if( cbp->cb == cb) {
                if( last_cbp == NULL)
                    enp->cb1 = NULL;
                else
                    last_cbp->next = cbp->next;
                free( cbp);
                break;
            }
        }
    }
}

pthread_mutex_unlock( &lsevents_listener_mutex);

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

```

7.2.4.6 void lsevents_run ()

Start up the thread and get out of the way.

Definition at line 390 of file lsevents.c.

```

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

```

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

Call the callback routines for the given event.

Parameters

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

Definition at line 73 of file lsevents.c.

```

{
    char event[LSEVENTS_EVENT_LENGTH];
    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);

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

    lsevents_queue[(lsevents_queue_on++) %
                   LSEVENTS_QUEUE_LENGTH].evp = strdup(event);

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

```

7.2.4.8 void* lsevents_worker (void * dummy)

Our worker.

Parameters

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

Definition at line 331 of file lsevents.c.

```

{
    char *event;
    lsevents_callbacks_t *cbi;

    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);

        //
        // Get our event name
        //
        event = lsevents_queue[(lsevents_queue_off+
                               +) % LSEVENTS_QUEUE_LENGTH].evp;

        //
        // 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);

        // call our callbacks
        //
        pthread_mutex_lock( &lsevents_listener_mutex);
        for( cbi = lsevents_register_event( event); cbi !=
            NULL; cbi = cbi->next ) {
            cbi->cb( event);
        }
    }
}

```

```

    pthread_mutex_unlock( &lsevents_listener_mutex);
    free( event);
}
return NULL;
}

```

7.2.5 Variable Documentation

7.2.5.1 struct hsearch_data lsevents_event_name_ht [static]

Definition at line 31 of file lsevents.c.

7.2.5.2 lsevents_event_names_t* lsevents_event_names = NULL [static]

Definition at line 60 of file lsevents.c.

7.2.5.3 pthread_mutex_t lsevents_listener_mutex [static]

mutex to protect the listener linked list

Definition at line 65 of file lsevents.c.

7.2.5.4 lsevents_listener_t* lsevents_listeners_p = NULL [static]

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

Definition at line 42 of file lsevents.c.

7.2.5.5 int lsevents_max_events = 1024 [static]

Definition at line 29 of file lsevents.c.

7.2.5.6 int lsevents_n_events = 0 [static]

Definition at line 30 of file lsevents.c.

7.2.5.7 lsevents_queue_t lsevents_queue[LSEVENTS_QUEUE_LENGTH] [static]

simple list of events

Definition at line 21 of file lsevents.c.

7.2.5.8 pthread_cond_t lsevents_queue_cond [static]

condition to pause the queue if needed

Definition at line 67 of file lsevents.c.

7.2.5.9 pthread_mutex_t lsevents_queue_mutex [static]

mutex to protect the event queue

Definition at line 66 of file lsevents.c.

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

next queue location to read

Definition at line 23 of file lsevents.c.

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

next queue location to write

Definition at line 22 of file lsevents.c.

7.2.5.12 `pthread_t lsevents_thread` `[static]`

thread to run the event queue

Definition at line 64 of file lsevents.c.

7.3 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_event_cb](#) (char *event)

Log most events.

- 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

7.3.1 Detailed Description

Logs messages to a file.

Date

2012

Author

Keith Brister

Copyright

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

7.3.2 Macro Definition Documentation

7.3.2.1 #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](#).

7.3.2.2 #define LSLOGGING_MSG_LENGTH 2048

Fixed maximum length messages to keep some form of sanity.

Definition at line 20 of file lslogging.c.

7.3.2.3 #define LSLOGGING_QUEUE_LENGTH 8192

Modest length queue.

Definition at line 30 of file lslogging.c.

7.3.3 Typedef Documentation

7.3.3.1 typedef struct lslogging_queue_struct lslogging_queue_t

Our log object: time and message.

7.3.4 Function Documentation

7.3.4.1 void lslogging_event_cb (char * event)

Log most events.

Definition at line 76 of file lslogging.c.

```

    {
        if ( strcmp( event, "Timer Update KVs" ) != 0 ) {
            lslogging_log_message( "EVENT: %s", event );
        }
    }

```

7.3.4.2 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" );
    }

```

7.3.4.3 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);
}

```

7.3.4.4 void lslogging_run ()

Start up the worker thread.

Definition at line 114 of file lslogging.c.

```

{
pthread_create( &lslogging_thread, NULL, &lslogging_worker
, NULL);
lslogging_log_message( "Start up");
lsevents_add_listener( ".+", lslogging_event_cb
);
}

```

7.3.4.5 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 85 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;
    msec = lslogging_queue[off].ltime.tv_nsec / 1000;
    fprintf( lslogging_file, "%s.%06u %s\n", tstr, msec,
            lslogging_queue[off].lmsg);
    fflush( lslogging_file);
}
}

```

7.3.5 Variable Documentation

7.3.5.1 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.

7.3.5.2 FILE* lslogging_file [static]

our log file object

Definition at line 17 of file lslogging.c.

7.3.5.3 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.

7.3.5.4 unsigned int lslogging_off = 0 [static]

next location to remove from the queue

Definition at line 34 of file lslogging.c.

7.3.5.5 unsigned int lslogging_on = 0 [static]

next location to add to the queue

Definition at line 33 of file lslogging.c.

7.3.5.6 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.

7.3.5.7 pthread_t lslogging_thread [static]

our thread

Definition at line 10 of file lslogging.c.

7.4 lspg.c File Reference

Postgresql support for the LS-CAT pgpmac project.


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

Data Structures

- 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
[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_allkvs_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- set a redis variable based on an updated kv pair*
- void [lspg_update_kvs_cb](#) (char *event)
- Perhaps update the px.kvs table in postgresql Should be triggered by a timer event.*
- void [lspg_starttransfer_init](#) ()
- void [lspg_starttransfer_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- void [lspg_starttransfer_call](#) (unsigned int nextsample, int [sample_detected](#), double ax, double ay, double az, double horz, double vert, double esttime)
- void [lspg_starttransfer_wait](#) ()
- void [lspg_starttransfer_done](#) ()
- int [lspg_starttransfer_all](#) (int *err, unsigned int nextsample, int sampledetected, double ax, double ay, double az, double horz, double vert, double esttime)
- void [lspg_getcurrentsampleid_init](#) ()
- void [lspg_getcurrentsampleid_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- get currentsampleid*
- void [lspg_getcurrentsampleid_call](#) ()
- unsigned int [lspg_getcurrentsampleid_read](#) ()
- void [lspg_getcurrentsampleid_wait_for_id](#) (unsigned int test)
- void [lspg_nextsample_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- Next Sample.*
- void [lspg_nextsample_init](#) ()
- Initialize the nextsample variable, mutex, and condition.*
- void [lspg_nextsample_call](#) ()
- Queue up a nextsample query.*
- void [lspg_nextsample_wait](#) ()
- Wait for the nextsample query to get processed.*
- void [lspg_nextsample_done](#) ()
- Called when the next shot query has been processed.*
- unsigned int [lspg_nextsample_all](#) (int *err)
- void [lspg_waitcryo_init](#) ()
- void [lspg_waitcryo_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- void [lspg_waitcryo_all](#) ()
- no need to get fancy with the wait cryo command It should not return until the robot is almost ready for air rights*
- void [lspg_demandairrights_init](#) ()
- initialize the demandairrights structure*
- void [lspg_demandairrights_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- handle the airrights response*
- void [lspg_demandairrights_call](#) ()
- call for airrights*
- void [lspg_demandairrights_wait](#) ()
- wait for the air rights request to return*
- void [lspg_demandairrights_all](#) ()
- do nothing until we get airrights*
- 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 diffractometer locking object
- void `lspg_lock_diffractionmeter_cb` (lspg_query_queue_t *qqp, PGresult *pgr)
Callback routine for a lock diffractometer query.
- void `lspg_lock_diffractionmeter_call` ()
Request that the database grab the diffractometer lock.
- void `lspg_lock_diffractionmeter_wait` ()
Wait for the diffractometer lock.
- void `lspg_lock_diffractionmeter_done` ()
Finish up the lock diffractometer call.
- void `lspg_lock_diffractionmeter_all` ()
Convenience function that combines lock diffractometer 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 be 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 convinence 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_preset_changed_cb](#) (char *event)
- void [lspg_check_preset_in_position_cb](#) (char *event)
- void [lspg_unset_current_preset_moving_cb](#) (char *event)
- void [lspg_set_scale_cb](#) (char *event)
Fix up xscale and yscale when zoom changes.
- void [lspg_sample_detector_cb](#) (char *event)
log magnet state
- void [lspg_init](#) ()
Initiallize 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_nextsample_t` `lspg_nextsample`
the very next sample
- `lspg_nextshot_t` `lspg_nextshot`
the nextshot object
- `lspg_getcenter_t` `lspg_getcenter`
the getcenter object
- `lspg_demandairrights_t` `lspg_demandairrights`
our demandairrights object
- `lspg_getcurrentsampleid_t` `lspg_getcurrentsampleid`
our currentsample id
- `lspg_starttransfer_t` `lspg_starttransfer`
start a sample transfer
- `lspg_waitcryo_t` `lspg_waitcryo`
signal the robot
- 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`

7.4.1 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](#).

7.4.2 Macro Definition Documentation

7.4.2.1 #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 50 of file [lspg.c](#).

7.4.2.2 #define LS_PG_STATE_IDLE 1

Definition at line 33 of file [lspg.c](#).

7.4.2.3 #define LS_PG_STATE_INIT -4

Definition at line 29 of file [lspg.c](#).

7.4.2.4 #define LS_PG_STATE_INIT_POLL -3

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

7.4.2.5 #define LS_PG_STATE_RECV 4

Definition at line 36 of file [lspg.c](#).

7.4.2.6 #define LS_PG_STATE_RESET -2

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

7.4.2.7 #define LS_PG_STATE_RESET_POLL -1

Definition at line 32 of file lspg.c.

7.4.2.8 #define LS_PG_STATE_SEND 2

Definition at line 34 of file lspg.c.

7.4.2.9 #define LS_PG_STATE_SEND_FLUSH 3

Definition at line 35 of file lspg.c.

7.4.3 Typedef Documentation**7.4.3.1 typedef struct lspg_lock_detector_struct lspg_lock_detector_t**

lock detector object Implements detector lock for exposure control

7.4.3.2 typedef struct lspg_lock_diffractionmeter_struct lspg_lock_diffractionmeter_t

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

7.4.3.3 typedef struct lspg_seq_run_prep_struct lspg_seq_run_prep_t

Data collection running object.

7.4.3.4 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.

7.4.4 Function Documentation**7.4.4.1 void lspg_allkvs_cb (lspg_query_queue_t * *qqp*, PGresult * *pgr*)**

set a redis variable based on an updated kv pair

Parameters

<i>qqp</i>	The query that elicited this response
<i>pgr</i>	The resonse from postgresql

Definition at line 279 of file lspg.c.

```

{
    int kvname_col, kvvalue_col, kvseq_col, kvdbrtype_col;
    int i;
    lsredis_obj_t *robj;

    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;
}

for( i=0; i<PQntuples( pgr); i++) {
    pthread_mutex_lock( &lsredis_mutex);
    while( lsredis_running == 0)
        pthread_cond_wait( &lsredis_cond, &lsredis_mutex
        );

    robj = _lsredis_get_obj( PQgetvalue( pgr, i, kvname_col));
    pthread_mutex_unlock( &lsredis_mutex);

    if( robj == NULL) {
        lslogging_log_message( "lspg_allkvs_cb: could not
        find redis object named '%s'", PQgetvalue( pgr, i, kvname_col));
        continue;
    }

    lsredis_setstr( robj, "%s", PQgetvalue( pgr, i, kvvalue_col))
    ;
}
}

```

7.4.4.2 char** lspg_array2ptrs (char * a)

returns a null terminated list of strings parsed from postgresql array

Definition at line 160 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] != '{' || a[strlen(a)-1] != '}')
        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) {
        lslogging_log_message( "lspg_array2ptrs: out of memory
        (acums)");
        exit( 1);
    }

    //
    // allocate storage for the pointer array and the null terminator
    //
    rtn = (char **)calloc( n+1, sizeof( char *));
    if( rtn == NULL) {
        lslogging_log_message( "lspg_array2ptrs: out of memory
        (rtn)");
        exit( 1);
    }
    rtni = 0;

    // Go through and create the individual strings
    sp = acums;
    *sp = 0;

    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;
                free( acums);
                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.
// Through out the last entry since this there is not resonable expectation
// that
// we should be parsing it anyway.
//
rtn[rtni] = NULL;
free( acums);
return( rtn);
}

```

7.4.4.3 void lspg_check_preset_in_position.cb (char * event)

Definition at line 1868 of file lspg.c.

```

{
    lspmac_motor_t *mp;
    char cp[64];
    int i;

    for( i=0; i<strlen( event); i++) {
        cp[i] = 0;
        if( event[i] == ' ')
            break;
        cp[i] = event[i];
    }
}

```

```

mp = lspmac_find_motor_by_name( cp);
if( mp == NULL) {
    return;
}
i = lsredis_find_preset_index_by_position
    ( mp);
lspg_query_push( NULL, "EXECUTE kvupdate(
    '%s.currentPreset,%d')", cp, i);
}

```

7.4.4.4 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 1338 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<PGntuples( pgr); i++) {
        sp = PQgetvalue( pgr, i, 0);
        if( sp != NULL && *sp != 0) {
            lspmac_SockSendDPLine( NULL, sp);
            //      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()");
        }
    }
}

```

7.4.4.5 void lspg_demandairrights.all ()

do nothing until we get airrights

Definition at line 655 of file lspg.c.

```

{
    lspg_demandairrights_call();
    lspg_demandairrights_wait();
    // there is no "done" version
}

```

7.4.4.6 void lspg_demandairrights.call ()

call for airrights

Definition at line 637 of file lspg.c.

```

    {
        pthread_mutex_lock( &lspg_demandairrights.mutex);
        lspg_demandairrights.new_value_ready = 0;
        pthread_mutex_unlock( &lspg_demandairrights.mutex);
        lspg_query_push( lspg_demandairrights.cb
            , "SELECT px.demandairrights()");
    }

```

7.4.4.7 void lspg_demandairrights.cb (lspg_query_queue_t * qqp, PGresult * pgr)

handle the airrights response

Definition at line 628 of file Ispg.c.

```

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

```

7.4.4.8 void lspg_demandairrights.init ()

initialize the demandairrights structure

Definition at line 620 of file Ispg.c.

```

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

```

7.4.4.9 void lspg_demandairrights.wait ()

wait for the air rights request to return

Definition at line 646 of file Ispg.c.

```

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

```

7.4.4.10 void lspg_flush ()

Flush psql output buffer (ie, send the query)

Definition at line 1368 of file Ispg.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;
}
}

```

7.4.4.11 void lspg_getcenter_all()

Convenience function to complete synchronous getcenter query.

Definition at line 1300 of file lspg.c.

```

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

```

7.4.4.12 void lspg_getcenter_call()

Request a getcenter query.

Definition at line 1276 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() ");
}

```

7.4.4.13 void lspg_getcenter_cb(lspg_query_queue_t * qq, PGresult * pgr)

Retrieve the data to center the crystal.

Definition at line 1211 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));
}

```

7.4.4.14 void lspg_getcenter_done ()

Done with getcenter query.

Definition at line 1294 of file lspg.c.

```

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

```

7.4.4.15 void lspg_getcenter_init ()

Initialize getcenter object.

Definition at line 1268 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);
}

```

7.4.4.16 void lspg_getcenter_wait ()

Wait for a getcenter query to return.

Definition at line 1286 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));
}

```

7.4.4.17 void lspg_getcurrentsampleid_call ()

Definition at line 466 of file lspg.c.

```

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

lspg_query_push( lspg_getcurrentsampleid_cb
, "SELECT px.getcurrentsampleid()");
}

```

7.4.4.18 void lspg_getcurrentsampleid_cb (lspg_query_queue_t * qqp, PGresult * pgr)

get currentsampleid

Definition at line 445 of file lspg.c.

```

    {
pthread_mutex_lock( &lspg_getcurrentsampleid.mutex
);

lspg_nextsample.new_value_ready = 1;
lspg_getcurrentsampleid.no_rows_returned
= PQntuples( pgr ) <= 0;
if( lspg_getcurrentsampleid.no_rows_returned
) {
    pthread_cond_signal( &lspg_getcurrentsampleid.cond
);
    pthread_mutex_unlock( &lspg_getcurrentsampleid.mutex
);
    return;
}

lspg_getcurrentsampleid.getcurrentsampleid_isnull
= PQgetisnull( pgr, 0, 0);
if( lspg_getcurrentsampleid.getcurrentsampleid_isnull
== 0)
    lspg_getcurrentsampleid.getcurrentsampleid
= strtol( PQgetvalue( pgr, 0, 0), NULL, 0);

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

```

7.4.4.19 void lspg_getcurrentsampleid_init ()

Definition at line 437 of file lspg.c.

```

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

```

7.4.4.20 unsigned int lspg_getcurrentsampleid_read ()

Definition at line 476 of file lspg.c.

```

{
    unsigned int rtn;
    pthread_mutex_lock( &lspg_getcurrentsampleid.mutex
    );
    while( lspg_getcurrentsampleid.new_value_ready
    == 0)
        pthread_cond_wait( &lspg_getcurrentsampleid.cond
        , &lspg_getcurrentsampleid.mutex);

    if( lspg_getcurrentsampleid.getcurrentsampleid_isnull
    )
        rtn = -1;
    else
        rtn = lspg_getcurrentsampleid.getcurrentsampleid
        ;
    pthread_mutex_unlock( &lspg_getcurrentsampleid.mutex
    );
    return rtn;
}

```

7.4.4.21 void lspg_getcurrentsampleid_wait_for_id (unsigned int test)

Definition at line 492 of file lspg.c.

```

{
    pthread_mutex_lock( &lspg_getcurrentsampleid.mutex
    );
    while( lspg_getcurrentsampleid.getcurrentsampleid
    != test)
        pthread_cond_wait( &lspg_getcurrentsampleid.cond
        , &lspg_getcurrentsampleid.mutex);

    pthread_mutex_unlock( &lspg_getcurrentsampleid.mutex
    );
}

```

7.4.4.22 void lspg_init ()

Initialize the lspg module.

Definition at line 1951 of file lspg.c.

```

{
    pthread_mutex_init( &lspg_queue_mutex, NULL);
    pthread_cond_init( &lspg_queue_cond, NULL);

    lspg_demandairrights_init();
    lspg_getcenter_init();
    lspg_getcurrentsampleid_init();
    lspg_lock_detector_init();
    lspg_lock_diffractionmeter_init();
    lspg_nextsample_init();
    lspg_nextshot_init();
    lspg_seq_run_prep_init();
    lspg_starttransfer_init();
    lspg_wait_for_detector_init();
    lspg_waitcryo_init();
}

```

7.4.4.23 void lspg_lock_detector_all ()

Detector lock convinence function.

Definition at line 1123 of file lspg.c.

```

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

```

7.4.4.24 void lspg_lock_detector_call ()

Request (demand) a detector lock.

Definition at line 1099 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() );
    }

```

7.4.4.25 void lspg_lock_detector_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Callback for when the detector lock has be grabbed.

Definition at line 1090 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));
    }

```

7.4.4.26 void lspg_lock_detector_done ()

Finish waiting.

Definition at line 1117 of file lspg.c.

```

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

```

7.4.4.27 void lspg_lock_detector_init ()

Initialize detector lock object.

Definition at line 1082 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);
    }

```


7.4.4.28 void lspg_lock_detector_wait ()

Wait for the detector lock.

Definition at line 1109 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));
}

```

7.4.4.29 void lspg_lock_diffractionmeter_all ()

Convenience function that combines lock diffractionmeter calls.

Definition at line 1064 of file lspg.c.

```

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

```

7.4.4.30 void lspg_lock_diffractionmeter_call ()

Request that the database grab the diffractionmeter lock.

Definition at line 1040 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()");
}

```

7.4.4.31 void lspg_lock_diffractionmeter_cb (lspg_query_queue_t * *qqp*, PGresult * *pgr*)

Callback routine for a lock diffractionmeter query.

Definition at line 1031 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));
}

```

7.4.4.32 void lspg_lock_diffractionmeter_done ()

Finish up the lock diffractionmeter call.

Definition at line 1058 of file lspg.c.

```

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

```

7.4.4.33 void lspg_lock_diffractionmeter_init ()

initialize the diffractionmeter locking object

Definition at line 1023 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);
    }

```

7.4.4.34 void lspg_lock_diffractionmeter_wait ()

Wait for the diffractionmeter lock.

Definition at line 1050 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));
    }

```

7.4.4.35 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 1725 of file lspg.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;
}
}

```

7.4.4.36 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 1309 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);
    }
}

```

7.4.4.37 unsigned int lspg_nextsample_all (int * err)

Definition at line 567 of file lspg.c.

```

{
    unsigned int rtn;

    lspg_nextsample_call();
    lspg_nextsample_wait();

    if( lspg_nextsample.no_rows_returned) {
        rtn = 0;
        *err = 1;
    } else {
        if( lspg_nextsample.nextsample_isnull) {
            rtn = 0;
            *err = 1;
        } else {
            rtn = lspg_nextsample.nextsample;
            *err = 0;
        }
    }
    lspg_nextsample_done();

    return rtn;
}

```

7.4.4.38 void lspg_nextsample_call()

Queue up a nextsample query.

Definition at line 544 of file lspg.c.

```

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

    lspg_query_push( lspg_nextsample.cb, "SELECT
        nextsample FROM px.nextsample()");
}

```

7.4.4.39 void lspg_nextsample.cb(lspg_query_queue_t * qqp, PGresult * pgr)

Next Sample.

Parameters

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

Definition at line 503 of file lspg.c.

```

{
    static int got_columns = 0;
    static int nextsample_col;
    pthread_mutex_lock( &(lspg_nextsample.mutex));

    lspg_nextsample.no_rows_returned = PQntuples(
        pgr) <= 0;
    if( lspg_nextsample.no_rows_returned) {
        lslogging_log_message( "lspg_nextsample.cb: no rows
            returned. This should never happen.");
        lspg_nextsample.new_value_ready = 1;
        pthread_cond_signal( &(lspg_nextsample.cond));
        pthread_mutex_unlock( &(lspg_nextsample.mutex));
        return;
    }

    if( got_columns == 0) {
        nextsample_col = PQfnumber( pgr, "nextsample");
        got_columns = 1;
    }

    lspg_nextsample.nextsample_isnull =
        PQgetisnull( pgr, 0, nextsample_col);
    if( lspg_nextsample.nextsample_isnull == 0)

```

```

    lspg_nextsample.nextsample = strtol( PQgetvalue(
        pgr, 0, nextsample_col), NULL, 0);

    lspg_nextsample.new_value_ready = 1;
    pthread_cond_signal( &(amp;lspg_nextsample.cond));
    pthread_mutex_unlock( &(amp;lspg_nextsample.mutex));
}

```

7.4.4.40 void lspg_nextsample_done ()

Called when the next shot query has been processed.

Definition at line 562 of file lspg.c.

```

{
    pthread_mutex_unlock( &(amp;lspg_nextsample.mutex));
}

```

7.4.4.41 void lspg_nextsample_init ()

Initialize the nextsample variable, mutex, and condition.

Definition at line 536 of file lspg.c.

```

memset( &lspg_nextsample, 0, sizeof( lspg_nextsample
));
pthread_mutex_init( &(amp;lspg_nextsample.mutex), NULL);
pthread_cond_init( &(amp;lspg_nextsample.cond), NULL);
}

```

7.4.4.42 void lspg_nextsample_wait ()

Wait for the nextsample query to get processed.

Definition at line 554 of file lspg.c.

```

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

```

7.4.4.43 void lspg_nextshot_call ()

Queue up a nextshot query.

Definition at line 923 of file lspg.c.

```

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

    lspg_query_push( lspg_nextshot_cb, "SELECT *
        FROM px.nextshot2()");
}

```

7.4.4.44 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 object `lspg_nextshot` set.

Parameters

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

Definition at line 668 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
    , dsomega_c);
if( lspg_nextshot.dsomega_isnull == 0)
    lspg_nextshot.dsomega = atof( PQgetvalue( pgr,0,
    dsomega_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));
}

```

7.4.4.45 void lspg_nextshot.done ()

Called when the next shot query has been processed.

Definition at line 941 of file lspg.c.

```

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

```

7.4.4.46 void lspg_nextshot.init ()

Initialize the nextshot variable, mutex, and condition.

Definition at line 915 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);
}

```

7.4.4.47 void lspg_nextshot_wait ()

Wait for the next shot query to get processed.

Definition at line 933 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));
}

```

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

Definition at line 1629 of file lspg.c.

```

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

```

7.4.4.49 void lspg_pg_connect ()

Connect to the pg server.

Definition at line 1636 of file lspg.c.

```

    {
int 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( NULL, "select pmac.md2_init()");
        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( NULL, "select pmac.md2_init()");
        ls_pg_state = LS_PG_STATE_IDLE;
    }
    break;
}
}
}

```

7.4.4.50 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 1528 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) {
        lspg_pg_state = LS_PG_STATE_RESET;
    }
    return;
}

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

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

if( lspg_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;

        lslogging_log_message( "lspg_pg_service: notify
        recieved %s", pgn->relnam);

        if( strstr( pgn->relnam, "_pmac") != NULL) {
            lspg_query_push( lspg_cmd_cb, "EXEVUTE
            md2_queue_next");
        } else if( strstr( pgn->relnam, "_diff") != NULL || strstr( pgn->
        relnam, "_run") != NULL) {
            lspg_query_push( lspg_nextaction_cb,
            "EXECUTE nextaction");
        } else if( strstr( pgn->relnam, "_sample") != NULL) {
            lspg_getcurrentsampleid_call();
        } else if( strstr( pgn->relnam, "_kvs") != NULL) {
            lspg_query_push( lspg_allkvs_cb, "
            EXECUTE getkvs");
        }
        PQfreemem( pgn);
    }
}

if( evt->revents & POLLOUT) {

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

    if( lspg_pg_state == LS_PG_STATE_RESET_POLL)
    {
        lspg_resetPoll_response = PQresetPoll( q);
        if( lspg_resetPoll_response ==
        PGRES_POLLING_FAILED) {
            lspg_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();
    }
}
}

```

7.4.4.51 void lspg_preset_changed_cb (char * event)

Definition at line 1846 of file lspg.c.

```

static char base[] = "Preset Changed ";
char *pn;
lsredis_obj_t *p;
char *v;

pn = strstr( event, base);
if( pn == NULL) {
    lslogging_log_message( "lspg_preset_changed_cb: Could
        not parse '%s'", event);
    return;
}
pn += strlen( base);

p = lsredis_get_obj( "%s", pn);
if( p == NULL) {
    lslogging_log_message( "lspg_preset_changed_cb: Could
        not find variable '%s'", pn);
    return;
}
v = lsredis_getstr( p);
lspg_query_push( NULL, "EXECUTE kvupdate('{%s,%s}':text[])",
    pn, v);
}

```

7.4.4.52 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 74 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;
}

```

7.4.4.53 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 127 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) %
        LS_PG_QUERY_QUEUE_LENGTH == lspg_query_queue_off %
        LS_PG_QUERY_QUEUE_LENGTH) {
        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);
};

```

7.4.4.54 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 98 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);
}

```

7.4.4.55 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 111 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;
}

```

7.4.4.56 void lspg_receive ()

Receive a result of a query.

Definition at line 1445 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->qs, 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);
    }
}
}

```

7.4.4.57 void lspg_run ()

Start 'er runnin'.

Definition at line 1970 of file lspg.c.

```

    {
pthread_create( &lspg_thread, NULL, lspg_worker, NULL);
lsevents_add_listener( "(appy|appz|capy|capz|scint) In
    Position",      lspg_check_preset_in_position_cb
    );
lsevents_add_listener( "(appy|appz|capy|capz|scint)
    Moving",      lspg_unset_current_preset_moving_cb
    );
lsevents_add_listener( "Preset Changed (.)",
    lspg_preset_changed_cb);
lsevents_add_listener( "Sample(Detected|Absent)",
    lspg_sample_detector_cb);
lsevents_add_listener( "Timer Update KVs",
    lspg_update_kvs_cb);
lsevents_add_listener( "cam.zoom In Position",
    lspg_set_scale_cb);
lstimer_set_timer( "Timer Update KVs", -1, 0, 500000000)
    ;
    }

```

7.4.4.58 void lspg_sample_detector_cb (char * event)

log magnet state

Definition at line 1939 of file lspg.c.

```

    {
int present;
if( strcmp( event, "SampleDetected") == 0)
    present = 1;
else
    present = 0;

lspg_query_push( NULL, "SELECT px.logmagnetstate(%s)", present
    ? "TRUE" : "FALSE");
    }

```

7.4.4.59 void lspg_send_next_query ()

send the next queued query to the DB server

Definition at line 1398 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;
    }
}
}
}

```

7.4.4.60 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 1194 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();
}

```

7.4.4.61 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 1160 of file lspg.c.

```

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

```

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

Callback for the seq_run_prep query.

Parameters

in	qqp	The query item that generated this callback
in	pgr	The result of the query

Definition at line 1148 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));
    }

```

7.4.4.63 void lspg_seq_run_prep.done ()

Indicate we are done waiting.

Definition at line 1188 of file lspg.c.

```

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

```

7.4.4.64 void lspg_seq_run_prep.init ()

Initialize the data collection object.

Definition at line 1140 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);
    }

```

7.4.4.65 void lspg_seq_run_prep.wait ()

Wait for seq run prep query to return.

Definition at line 1180 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));
    }

```

7.4.4.66 void lspg_set_scale_cb (char * event)

Fix up xscale and yscale when zoom changes.

Definition at line 1912 of file lspg.c.

```

{
    int mag;
    lsredis_obj_t *px, *py;
    char *sx, *sy;

    //
    // There is already a call back to set the redis variables xScale and yScale
    // we just need to set the KV's
    //

    mag = lspmac_getPosition( zoom );

    px = lsredis_get_obj( "cam.zoom.%d.ScaleX", mag );
    sx = lsredis_getstr( px );

    py = lsredis_get_obj( "cam.zoom.%d.ScaleY", mag );
    sy = lsredis_getstr( py );

    lspg_query_push( NULL, "EXECUTE kvupdate(
        '{cam.xScale,%s,cam.yScale,%s}' )", sx, sy );
    free( sx );
    free( sy );
}

```

7.4.4.67 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 1506 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 ));
}

```

7.4.4.68 int lspg_starttransfer_all (int * err, unsigned int nextsample, int sampledetected, double ax, double ay, double az, double horz, double vert, double esttime)

Definition at line 421 of file lspg.c.

```

{
    int rtn;

    lspg_starttransfer_call( nextsample, sampledetected,
        ax, ay, az, horz, vert, esttime );
    lspg_starttransfer_wait();
    if( lspg_starttransfer.no_rows_returned ||

```

```

    lspg_starttransfer.starttransfer != 1) {
    *err = 1;
} else {
    *err = 0;
    rtn = lspg_starttransfer.starttransfer;
}
lspg_starttransfer_done();

return rtn;
}

```

7.4.4.69 void `lspg_starttransfer_call` (unsigned int *nextsample*, int *sample_detected*, double *ax*, double *ay*, double *az*, double *horz*, double *vert*, double *esttime*)

Definition at line 401 of file `lspg.c`.

```

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

lspg_query_push( lspg_starttransfer_cb, "
    SELECT px.starttransfer( %d, %d, %.3f, %.3f, %.3f, %.3f, %.3f, %.3f",
        nextsample, sample_detected, ax, ay, az, horz
        , vert, esttime);
}

```

7.4.4.70 void `lspg_starttransfer_cb` (`lspg_query_queue_t` * *qqp*, `PGresult` * *pgr*)

Parameters

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

Definition at line 380 of file `lspg.c`.

```

{
pthread_mutex_lock( &(lspg_starttransfer.mutex));

lspg_starttransfer.new_value_ready = 1;
if( PQntuples( pgr) <=0) {
    lspg_starttransfer.no_rows_returned = 0;
    lspg_starttransfer.starttransfer = 0;
} else {
    lspg_starttransfer.no_rows_returned = 1;
    if( PQgetisnull( pgr, 0, 0) || strtol( PQgetvalue( pgr, 0, 0), NULL, 0) !=
        1)
        lspg_starttransfer.starttransfer = 0;
    else
        lspg_starttransfer.starttransfer = 1;
}
pthread_cond_signal( &(lspg_starttransfer.cond));
pthread_mutex_unlock( &(lspg_starttransfer.mutex));
}

```

7.4.4.71 void `lspg_starttransfer_done` ()

Definition at line 416 of file `lspg.c`.

```

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

```

7.4.4.72 void `lspg_starttransfer_init` ()

Definition at line 374 of file `lspg.c`.

```

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

```

7.4.4.73 void lspg_starttransfer_wait ()

Definition at line 410 of file lspg.c.

```

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

```

7.4.4.74 void lspg_unset_current_preset_moving_cb (char * event)

Definition at line 1889 of file lspg.c.

```

    {
        lspmac_motor_t *mp;
        char cp[64];
        int i;

        for( i=0; i<strlen( event); i++) {
            cp[i] = 0;
            if( event[i] == ' ' )
                break;
            cp[i] = event[i];
        }

        mp = lspmac_find_motor_by_name( cp);
        if( mp == NULL) {
            lslogging_log_message( "
                lspg_unset_current_reset_moving_cb: Could not find motor '%s'", cp);
            return;
        }
        lspg_query_push( NULL, "EXECUTE kvupdate(
            '{%s.currentPreset,-1}')" , cp);
    }

```

7.4.4.75 void lspg_update_kvs_cb (char * event)

Perhaps update the px.kvs table in postgresql Should be triggered by a timer event.

Definition at line 317 of file lspg.c.

```

    {
        static char s[LS_PG_QUERY_STRING_LENGTH - 64], *fmt;
        int i, need_comma, n;
        lspmac_motor_t *mp;
        int updateme;
        double new_value;

        s[0] = 0;
        need_comma = 0;

        for( i=0; i<lspmac_nmotors; i++) {
            mp = &(lspmac_motors[i]);
            pthread_mutex_lock( &mp->mutex);
            if( fabs(mp->reported_pg_position - mp->position
                ) >= lsredis_getd(mp->update_resolution)) {
                new_value = mp->position;
                mp->reported_pg_position = mp->position;
                fmt = lsredis_getstr( mp->redis_fmt); //
                borrow the redis format
                updateme = 1;
            } else {

```

```

        updateme = 0;
    }
    pthread_mutex_unlock( &mp->mutex);
    if( !updateme)
        continue;

    n = strlen( s);
    snprintf( &(s[n]), sizeof(s)-n-1, "%s%s.position,", need_comma++ ? ", " : ""
        , mp->name);

    n = strlen( s);
    snprintf( &(s[n]), sizeof(s)-n-1, fmt, new_value);

    //
    // And again for the original remote interface
    // We'll be able to remove this, someday
    //
    n = strlen( s);
    snprintf( &(s[n]), sizeof(s)-n-1, ",%s,", mp->name);

    n = strlen( s);
    snprintf( &(s[n]), sizeof(s)-n-1, fmt, new_value);
    free( fmt);

    n = strlen( s);
    if( n >= sizeof(s) - 64) {
        lspg_query_push( NULL, "EXECUTE kvupdate('{%s}')" , s);
        s[0] = 0;
        need_comma = 0;
    }
}

if( strlen(s)) {
    lspg_query_push( NULL, "EXECUTE kvupdate('{%s}')" , s);
}
}

```

7.4.4.76 void lspg_wait_for_detector.all ()

Combined call to wait for the detector.

Definition at line 1004 of file lspg.c.

```

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

```

7.4.4.77 void lspg_wait_for_detector.call ()

initiate the wait for detector query

Definition at line 978 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()");
}

```

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

Callback for the wait for detector query.

Definition at line 969 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
));
}

```

7.4.4.79 void lspg_wait_for_detector_done ()

Done waiting for the detector.

Definition at line 997 of file lspg.c.

```

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

```

7.4.4.80 void lspg_wait_for_detector_init ()

initialize the detector timing object

Definition at line 961 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);
}

```

7.4.4.81 void lspg_wait_for_detector_wait ()

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

Definition at line 989 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));
}

```

7.4.4.82 void lspg_waitcryo_all ()

no need to get fancy with the wait cryo command It should not return until the robot is almost ready for air rights

Definition at line 606 of file lspg.c.

```

{
pthread_mutex_lock( &lspg_waitcryo.mutex);
lspg_waitcryo.new_value_ready = 0;

lspg_query_push( lspg_waitcryo_cb, "SELECT
px.waitcryo()");
}

```

```

while( lspg_waitcryo.new_value_ready == 0)
    pthread_cond_wait( &lspg_waitcryo.cond, &lspg_waitcryo
        .mutex);

pthread_mutex_unlock( &lspg_waitcryo.mutex);
}

```

7.4.4.83 void lspg_waitcryo.cb(lspg_query_queue_t * qqp, PGresult * pgr)

Definition at line 596 of file lspg.c.

```

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

```

7.4.4.84 void lspg_waitcryo.init()

Definition at line 590 of file lspg.c.

```

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

```

7.4.4.85 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 1776 of file lspg.c.

```

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

    //
    // block ordinary signal mechanism
    //
    sigemptyset( &our_sigset);
    sigaddset( &our_sigset, SIGUSR1);
    pthread_sigmask(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 conneceted
    //
    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--;
}
}
}

```

7.4.5 Variable Documentation

7.4.5.1 `int ls_pg_state = LS_PG_STATE_INIT` [static]

State of the lspg state machine.

Definition at line 38 of file lspg.c.

7.4.5.2 `PostgresPollingStatusType lspg_connectPoll_response` [static]

Used to determine state while connecting.

Definition at line 59 of file lspg.c.

7.4.5.3 `lspg_demandairrights_t lspg_demandairrights`

our demandairrights object

Definition at line 65 of file lspg.c.

7.4.5.4 `lspg_getcenter_t lspg_getcenter`

the getcenter object

Definition at line 64 of file lspg.c.

7.4.5.5 `lspg_getcurrentsampleid_t lspg_getcurrentsampleid`

our currentsample id

Definition at line 66 of file lspg.c.

7.4.5.6 `lspg_lock_detector_t lspg_lock_detector` `[static]`

Definition at line 1078 of file `lspg.c`.

7.4.5.7 `lspg_lock_diffractionmeter_t lspg_lock_diffractionmeter` `[static]`

Definition at line 1019 of file `lspg.c`.

7.4.5.8 `lspg_nextsample_t lspg_nextsample`

the very next sample

Definition at line 62 of file `lspg.c`.

7.4.5.9 `lspg_nextshot_t lspg_nextshot`

the nextshot object

Definition at line 63 of file `lspg.c`.

7.4.5.10 `lspg_query_queue_t lspg_query_queue[LS_PG_QUERY_QUEUE_LENGTH]` `[static]`

Our query queue.

Definition at line 51 of file `lspg.c`.

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

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

Definition at line 53 of file `lspg.c`.

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

Next position to add something to the queue.

Definition at line 52 of file `lspg.c`.

7.4.5.13 `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 54 of file `lspg.c`.

7.4.5.14 `pthread_cond_t lspg_queue_cond` `[static]`

keeps the queue from overflowing

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

7.4.5.15 `pthread_mutex_t lspg_queue_mutex` `[static]`

keep the queue from getting tangled

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

7.4.5.16 `PostgresPollingStatusType lspg_resetPoll_response` `[static]`

Used to determine state while reconnecting.

Definition at line 60 of file `lspg.c`.

7.4.5.17 `lspg_seq_run_prep_t lspg_seq_run_prep` `[static]`

Definition at line 1136 of file `lspg.c`.

7.4.5.18 `lspg_starttransfer_t lspg_starttransfer`

start a sample transfer

Definition at line 67 of file `lspg.c`.

7.4.5.19 `pthread_t lspg_thread` `[static]`

our worker thread

Definition at line 41 of file `lspg.c`.

7.4.5.20 `lspg_wait_for_detector_t lspg_wait_for_detector` `[static]`

Instance of the detector timing object.

Definition at line 957 of file `lspg.c`.

7.4.5.21 `lspg_waitcryo_t lspg_waitcryo`

signal the robot

Definition at line 68 of file `lspg.c`.

7.4.5.22 `struct pollfd lspgfd` `[static]`

our poll info

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

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

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

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

7.4.5.24 PGconn* q = NULL [static]

Database connector.

Definition at line 58 of file lspg.c.

7.5 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.
- struct [lspmac_ascii_buffers_struct](#)
- struct [lspmac_dpascii_queue_struct](#)
- struct [lspmac_combined_move_struct](#)

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_MAX_MOTORS](#) 48
- #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 10000.0`
Minimum time between commands to the pmac.
- `#define PMAC_CMD_QUEUE_LENGTH 2048`
Size of the PMAC command queue.
- `#define LSPMAC_DPASCII_QUEUE_LENGTH 1024`

Typedefs

- `typedef struct md2StatusStruct md2_status_t`
The block of memory retrieved in a status request.
- `typedef struct lspmac_ascii_buffers_struct lspmac_ascii_buffers_t`
- `typedef struct lspmac_dpascii_queue_struct lspmac_dpascii_queue_t`
- `typedef struct lspmac_combined_move_struct lspmac_combined_move_t`

Functions

- `void lspmac_get_ascii (char *)`
Forward declaration.
- `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.
- `void lspmac_reset_queue ()`
Clear the queue as part of PMAC reinitialization.
- `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, char *data, void (*responseCB)(pmac_cmd_queue_t *, int, char *), int no_reply, char *event)`

- 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](#) (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, char *buff)
- Receive a reply that does not require multiple buffers.*

 - void [lspmac_SendControlReplyPrintCB](#) (pmac_cmd_queue_t *cmd, int nreceived, 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, 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 *event, char *fmt,...)
- Send a one line command.*

 - [pmac_cmd_queue_t](#) * [lspmac_SockSendline_nr](#) (char *event, char *fmt,...)
- Send a command and ignore the response.*

 - [pmac_cmd_queue_t](#) * [lspmac_SockSendControlCharPrint](#) (char *event, 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.*

 - int [lspmac_getBIPosition](#) (lspmac_bi_t *bip)
- get binary input value*

 - void [lspmac_get_status_cb](#) (pmac_cmd_queue_t *cmd, int nreceived, 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_more_ascii_cb](#) (pmac_cmd_queue_t *cmd, int nreceived, char *buff)
- we are expecting more characters from the DPRAM ASCII interface*

 - void [lspmac_get_ascii_cb](#) (pmac_cmd_queue_t *cmd, int nreceived, char *buff)
- service the ascii buffer request response*

- void [lspmac_asciicmdCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, char *buf)
PMAC has received our ascii command request Now see when it is ready for the next one.
- void [lspmac_SockSendDPline](#) (char *event, char *fmt,...)
prepare (queue up) a line to send the dpram ascii command interface
- void [lspmac_SockSendDPControlCharCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, char *buf)
- void [lspmac_SockSendDPControlChar](#) (char *event, char c)
use dpram ascii interface to send a control character
- void [lspmac_SockSendDPqueue](#) ()
- void [lspmac_abort](#) ()
abort motion and try to recover
- void [lspmac_GetAllIVarsCB](#) ([pmac_cmd_queue_t](#) *cmd, int nreceived, 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, 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](#) (char *event, void(*responseCB)([pmac_cmd_queue_t](#) *, int, char *), char *fmt,...)
PMAC command with call back.
- void [lspmac_next_state](#) ()
State machine logic.
- void * [lspmac_worker](#) (void *dummy)
Our lspmac worker thread.
- int [lspmac_movedac_queue](#) ([lspmac_motor_t](#) *mp, double requested_position)
Move method for dac motor objects (ie, lights)
- int [lspmac_movezoom_queue](#) ([lspmac_motor_t](#) *mp, double requested_position)
Move method for the zoom motor.
- int [lspmac_move_preset_queue](#) ([lspmac_motor_t](#) *mp, char *preset_name)
Move a given motor to one of its preset positions.
- int [lspmac_test_preset](#) ([lspmac_motor_t](#) *mp, char *preset_name, double tolerance)
see if the motor is within tolerance of the preset 1 means yes, it is 0 mean no it isn't or that the preset was not found
- int [lspmac_moveabs_fshut_queue](#) ([lspmac_motor_t](#) *mp, double requested_position)
Move method for the fast shutter.
- int [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
- int [lspmac_moveabs_frontlight_oo_queue](#) ([lspmac_motor_t](#) *mp, double pos)
"move" frontlight on/off
- int [lspmac_moveabs_flight_factor_queue](#) ([lspmac_motor_t](#) *mp, double pos)
- int [lspmac_moveabs_blight_factor_queue](#) ([lspmac_motor_t](#) *mp, double pos)
- void [lspmac_video_rotate](#) (double secs)
Special motion program to collect centering video.
- int [lspmac_set_motion_flags](#) (int *mmaskp, [lspmac_motor_t](#) *mp_1,...)
Set the coordinate system motion flags (m5075) for the null terminated list of motors that we are planning on running a motion program with.
- int [lspmac_est_move_time](#) (double *est_time, int *mmaskp, [lspmac_motor_t](#) *mp_1, int jog_1, char *preset_1, double end_point_1,...)

- Move the motors and estimate the time it'll take to finish the job.*

 - int `lspmac_est_move_time_wait` (double `move_time`, int `cmask`, `lspmac_motor_t` *`mp_1`,...)
wait for motion to stop returns non-zero if the wait timed out
- int `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 Returns non-zero on abort, zero if OK.
- int `lspmac_move_or_jog_preset_queue` (`lspmac_motor_t` *`mp`, char *`preset`, int `use_jog`)
move using a preset value returns 0 on success, non-zero on error
- int `lspmac_moveabs_queue` (`lspmac_motor_t` *`mp`, double `requested_position`)
Use coordinate system motion program, if available, to move motor to requested position.
- int `lspmac_jogabs_queue` (`lspmac_motor_t` *`mp`, double `requested_position`)
Use jog to move motor to requested position.
- int `lspmac_moveabs_wait` (`lspmac_motor_t` *`mp`, double `timeout_secs`)
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`, int(*`moveAbs`)(`lspmac_motor_t` *, double), int(*`jogAbs`)(`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`, int(*`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`, int(*`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_maybe_turn_on_dryer_cb` (char *`event`)
Maybe start drying off the scintillator.
 - void `lspmac_scint_maybe_turn_off_dryer_cb` (char *`event`)
Maybe stop 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_maybe_move_sample_cb` (char *`event`)
Perhaps we need to move the sample out of the way.
 - void `lspmac_scint_maybe_return_sample_cb` (char *`event`)
Perhaps we need to return the sample to the beam.
 - void `lspmac_scint_dried_cb` (char *`event`)

- *Turn off the dryer.*
- void [lspmac_zoom_lut_setup](#) ()
Set up lookup table for zoom.
- void [lspmac_flight_lut_setup](#) ()
Set up lookup table for flight.
- void [lspmac_blight_lut_setup](#) ()
Set up lookup table for blight.
- void [lspmac_fscint_lut_setup](#) ()
Set up lookup table for fscint.
- [lspmac_motor_t * lspmac_find_motor_by_name](#) (char *name)
- void [lspmac_command_done_cb](#) (char *event)
- void [lspmac_run](#) ()
Start up the lspmac thread.

Variables

- static int [ls_pmac_state](#) = LS_PMAC_STATE_DETACHED
Current state of the PMAC communications state machine.
- 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 pthread_mutex_t [lspmac_ascii_mutex](#)
Keep too many processes from sending commands at once.
- static int [lspmac_ascii_busy](#) = 0
flag for condition to wait for
- 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` [32]
array of binary inputs
- int `lspmac_nbis` = 0
number of active binary inputs
- `lspmac_motor_t lspmac_motors` [LSPMAC_MAX_MOTORS]
All our motors.
- int `lspmac_nmotors` = 0
The number of motors we manage.
- struct hsearch_data `motors_ht`
A hash table to find motors by name.
- `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 * smart_mag_oo](#)
Smart Magnet on/off.
- [lspmac_motor_t * blight_ud](#)
Back light Up/Down actuator.
- [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_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_bi_t * lp_air](#)
Low pressure air OK.
- [lspmac_bi_t * hp_air](#)
High pressure air OK.
- [lspmac_bi_t * cryo_switch](#)
that little toggle switch for the cryo
- [lspmac_bi_t * blight_down](#)
Backlight is down.
- [lspmac_bi_t * blight_up](#)
Backlight is up.
- [lspmac_bi_t * cryo_back](#)
cryo is in the back position
- [lspmac_bi_t * fluor_back](#)
fluor is in the back position
- [lspmac_bi_t * sample_detected](#)
smart magnet detected sample
- [lspmac_bi_t * etel_ready](#)
ETEL is ready.
- [lspmac_bi_t * etel_on](#)
ETEL is on.
- [lspmac_bi_t * etel_init_ok](#)
ETEL initialized OK.
- [lspmac_bi_t * minikappa_ok](#)
Minikappa is OK (whatever that means)
- [lspmac_bi_t * smart_mag_on](#)
smart magnet is on
- [lspmac_bi_t * arm_parked](#)
(whose arm? parked where?)
- [lspmac_bi_t * shutter_open](#)
shutter is open (note in pmc says this is a slow input)
- [lspmac_bi_t * smart_mag_err](#)

- smart magnet error (coil broken perhaps)*
- `lspmac_bi_t * smart_mag_off`
- smart magnet is off*
- 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.*
- static `lspmac_ascii_buffers_t lspmac_ascii_buffers`
- pthread_mutex_t `lspmac_ascii_buffers_mutex`
- static `lspmac_dpascii_queue_t lspmac_dpascii_queue` [LSPMAC_DPASCII_QUEUE_LENGTH]
- static uint32_t `lspmac_dpascii_on` = 0
- static uint32_t `lspmac_dpascii_off` = 0

7.5.1 Detailed Description

Routines concerned with communication with PMAC. Test suite for the pgpmac routines.

```
\date 2012 - 2013
\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.

Most of these states are to deal with the "serial-port" style of communications. Things are surprisingly simple for the double buffer ascii and control character methods.

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

Date

2013

Author

Keith Brister

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A place to put unit tests.

Definition in file [lspmac.c](#).**7.5.2 Macro Definition Documentation****7.5.2.1 #define LS_PMAC_STATE_CR 7**

Definition at line 52 of file lspmac.c.

7.5.2.2 #define LS_PMAC_STATE_DETACHED 0

Definition at line 45 of file lspmac.c.

7.5.2.3 #define LS_PMAC_STATE_GB 10

Definition at line 55 of file lspmac.c.

7.5.2.4 #define LS_PMAC_STATE_GMR 6

Definition at line 51 of file lspmac.c.

7.5.2.5 #define LS_PMAC_STATE_IDLE 1

Definition at line 46 of file lspmac.c.

7.5.2.6 #define LS_PMAC_STATE_RESET -1

Definition at line 44 of file lspmac.c.

7.5.2.7 #define LS_PMAC_STATE_RR 8

Definition at line 53 of file lspmac.c.

7.5.2.8 #define LS_PMAC_STATE_SC 2

Definition at line 47 of file lspmac.c.

7.5.2.9 #define LS_PMAC_STATE_WACK 5

Definition at line 50 of file lspmac.c.

7.5.2.10 #define LS_PMAC_STATE_WACK_CC 4

Definition at line 49 of file lspmac.c.

7.5.2.11 #define LS_PMAC_STATE_WACK_NFR 3

Definition at line 48 of file lspmac.c.

7.5.2.12 #define LS_PMAC_STATE_WACK_RR 9

Definition at line 54 of file lspmac.c.

7.5.2.13 #define LS_PMAC_STATE_WCR 11

Definition at line 56 of file lspmac.c.

7.5.2.14 #define LS_PMAC_STATE_WGB 12

Definition at line 57 of file lspmac.c.

7.5.2.15 #define LSPMAC_DPASCII_QUEUE_LENGTH 1024

Definition at line 367 of file lspmac.c.

7.5.2.16 #define LSPMAC_MAX_MOTORS 48

Definition at line 94 of file lspmac.c.

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

Regex to pick out preset name and corresponding position.

Definition at line 150 of file lspmac.c.

7.5.2.18 #define PMAC_CMD_QUEUE_LENGTH 2048

Size of the PMAC command queue.
Definition at line 194 of file lspmac.c.

7.5.2.19 #define pmac_cmd_size 8

PMAC command size in bytes.
Definition at line 160 of file lspmac.c.

7.5.2.20 #define PMAC_MIN_CMD_TIME 10000.0

Minimum time between commands to the pmac.
Definition at line 190 of file lspmac.c.

7.5.2.21 #define PMACPORT 1025

The PMAC (only) listens on this port.
Definition at line 154 of file lspmac.c.

7.5.2.22 #define VR_CTRL_RESPONSE 0xc4

Definition at line 176 of file lspmac.c.

7.5.2.23 #define VR_DOWNLOAD 0x40

Definition at line 163 of file lspmac.c.

7.5.2.24 #define VR_FWDOWNLOAD 0xcb

Definition at line 180 of file lspmac.c.

7.5.2.25 #define VR_IPADDRESS 0xe0

Definition at line 181 of file lspmac.c.

7.5.2.26 #define VR_PMAC_FLUSH 0xb3

Definition at line 167 of file lspmac.c.

7.5.2.27 #define VR_PMAC_GETBUFFER 0xc5

Definition at line 177 of file lspmac.c.

7.5.2.28 #define VR_PMAC_GETLINE 0xb1

Definition at line 166 of file lspmac.c.

7.5.2.29 #define VR_PMAC_GETMEM 0xb4

Definition at line 168 of file lspmac.c.

7.5.2.30 #define VR_PMAC_GETRESPONSE 0xbf

Definition at line 174 of file lspmac.c.

7.5.2.31 #define VR_PMAC_PORT 0xbe

Definition at line 173 of file lspmac.c.

7.5.2.32 #define VR_PMAC_READREADY 0xc2

Definition at line 175 of file lspmac.c.

7.5.2.33 #define VR_PMAC_SENDCTRLCHAR 0xb6

Definition at line 170 of file lspmac.c.

7.5.2.34 #define VR_PMAC_SENDLINE 0xb0

Definition at line 165 of file lspmac.c.

7.5.2.35 #define VR_PMAC_SETBIT 0xba

Definition at line 171 of file lspmac.c.

7.5.2.36 #define VR_PMAC_SETBITS 0xbb

Definition at line 172 of file lspmac.c.

7.5.2.37 #define VR_PMAC_SETMEM 0xb5

Definition at line 169 of file lspmac.c.

7.5.2.38 #define VR_PMAC_WRITEBUFFER 0xc6

Definition at line 178 of file lspmac.c.

7.5.2.39 #define VR_PMAC_WRITEERROR 0xc7

Definition at line 179 of file lspmac.c.

7.5.2.40 #define VR_UPLOAD 0xc0

Definition at line 162 of file lspmac.c.

7.5.3 Typedef Documentation

7.5.3.1 typedef struct lspmac_ascii_buffers_struct lspmac_ascii_buffers_t

7.5.3.2 typedef struct lspmac_combined_move_struct lspmac_combined_move_t

7.5.3.3 typedef struct lspmac_dpascii_queue_struct lspmac_dpascii_queue_t

7.5.3.4 typedef struct md2StatusStruct md2_status_t

The block of memory retrieved in a status request.

7.5.4 Function Documentation

7.5.4.1 void lspmac_motor_init(lspmac_motor_t * d, char * name)

Helper function for the init calls.

Definition at line 3473 of file lspmac.c.

```

{
    lspmac_nmotors++;

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

    d->magic          = LSPMAC_MAGIC_NUMBER;
    d->name           = strdup(name);
    d->active         = lsredis_get_obj( "%s.active",
        d->name);
    d->active_init    = lsredis_get_obj( "
        %s.active_init", d->name);
    d->axis           = lsredis_get_obj( "%s.axis",
        d->name);
    d->coord_num      = lsredis_get_obj( "
        %s.coord_num", d->name);
    d->home           = lsredis_get_obj( "%s.home",
        d->name);
    d->inactive_init  = lsredis_get_obj( "
        %s.inactive_init", d->name);
    d->in_position_band = lsredis_get_obj( "
        %s.in_position_band", d->name);
    d->redis_fmt      = lsredis_get_obj( "%s.format",
        d->name);
    d->max_accel      = lsredis_get_obj( "
        %s.max_accel", d->name);
    d->max_speed      = lsredis_get_obj( "
        %s.max_speed", d->name);
    d->max_pos        = lsredis_get_obj( "
        %s.maxPosition", d->name);
    d->min_pos        = lsredis_get_obj( "
        %s.minPosition", d->name);
    d->motor_num      = lsredis_get_obj( "
        %s.motor_num", d->name);
    d->neg_limit_hit   = lsredis_get_obj( "
        %s.negLimitSet", d->name);
    d->neutral_pos     = lsredis_get_obj( "
        %s.neutralPosition", d->name);
    d->redis_position  = lsredis_get_obj( "
        %s.position", d->name);
    d->pos_limit_hit   = lsredis_get_obj( "
        %s.posLimitSet", d->name);
    d->precision       = lsredis_get_obj( "
        %s.precision", d->name);
    d->printf_fmt      = lsredis_get_obj( "
        %s.printf", d->name);
    d->status_str      = lsredis_get_obj( "
        %s.status_str", d->name);
    d->u2c             = lsredis_get_obj( "%s.u2c",
        d->name);
    d->unit           = lsredis_get_obj( "%s.unit",
        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;
d->reported_position = INFINITY;
d->reported_pg_position= INFINITY;

lsevents_preregister_event( "%s queued", d->name
);
lsevents_preregister_event( "%s command accepted",
d->name);

lsredis_load_presets( d->name);
}

```

7.5.4.2 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 553 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);
}

```

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

Prints a hex dump of the given data.

Used to debug packet data.

Parameters

in	n	Number of bytes passed in s
in	s	Data to dump

Definition at line 526 of file lspmac.c.

```

{
    int i;          // row counter
    int j;          // column counter
    unsigned char outs[128], outs1[4];

    for( i=0; n > 0; i++) {

        sprintf( (char *)outs, "%04d: ", 16*i);
        for( j=0; j<16 && n > 0; j++) {
            if( j==8)
                strcat( (char *)outs, " ");

```

```

        sprintf( (char *)outs1, " %02x", *(s + 16*i + j));
        strcat( (char *)outs, (char *)outs1);
        n--;
    }
    lslogging_log_message( "hex_dump: %s", outs);
}
}

```

7.5.4.4 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 574 of file lspmac.c.

```

{
    int psock;                // our socket: value stored in pmacfd.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;
}

```

7.5.4.5 void lspmac_abort ()

abort motion and try to recover

Definition at line 2031 of file lspmac.c.

```

    {
        //
        // Stop everything! (consider ^O instead of ^A)
        //
        lspmac_SockSendDPControlChar( "Abort Request", 0
            x01);

        //
        // and reset motion flag
        //
        lspmac_SockSendDPLine( "Reset", "%s", "M5075=0");
    }

```

7.5.4.6 void lspmac_asciicmdCB (pmac_cmd_queue_t * cmd, int nreceived, char * buf)

PMAC has received our ascii command request Now see when it is ready for the next one.

Definition at line 1962 of file lspmac.c.

```

    {
        lspmac_get_ascii( cmd->event);
    }

```

7.5.4.7 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 3922 of file lspmac.c.

```

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

```

7.5.4.8 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 3915 of file lspmac.c.

```

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

```

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

Initialize binary input.

Definition at line 3652 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;

        lsevents_preregister_event( "%s", d->changeEventOn
        );
        lsevents_preregister_event( "%s", d->changeEventOff
        );

        return d;
    }

```

7.5.4.10 `void lspmac_blight_lut_setup()`

Set up lookup table for blight.

Definition at line 4094 of file `lspmac.c`.

```

    {
        int i;
        lsredis_obj_t *p;

        pthread_mutex_lock( &blight->mutex);

        blight->nlut = 11;
        blight->lut = calloc( 2 * blight->nlut, sizeof( double));
        if( blight->lut == NULL) {
            lslogging_log_message( "lspmac_blight_lut_setup: out
            of memory");
            exit( -1);
        }

        blight->lut[0] = 0;
        blight->lut[1] = 0;

        for( i=1; i<blight->nlut; i++) {
            p = lsredis_get_obj( "cam.zoom.%d.LightIntensity", i);
            if( p==NULL || strlen( lsredis_getstr(p)) == 0) {
                free( blight->lut);
                blight->lut = NULL;
                blight->nlut = 0;
                pthread_mutex_unlock( &blight->mutex);
                lslogging_log_message( "lspmac_blight_lut_setup:
                cannot find MotorPosition element for cam.blight level %d", i);
                return;
            }
            blight->lut[2*i] = i;
            blight->lut[2*i+1] = 20000.0 * lsredis_getd( p) / 100.
            0;
        }
        for( i=0; i<blight->nlut; i++) {
            lslogging_log_message( "lspmac_blight_lut_setup: i:
            %d x: %f y: %f y(lut): %f x(rlut): %f",
            i, blight->lut[2*i], blight->lut[2
            *i+1],
            lspmac_lut( blight->nlut, blight
            ->lut, blight->lut[2*i]),
            lspmac_rlut( blight->nlut,
            blight->lut, blight->lut[2*i+1])
            );
        }
        pthread_mutex_unlock( &blight->mutex);
    }

```

7.5.4.11 `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 3581 of file `lspmac.c`.

```

{
    _lspmac_motor_init( d, name);

    d->moveAbs      = lspmac_moveabs_bo_queue;
    d->jogAbs       = 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;

    lsevents_preregister_event( "%s 1", d->name);
    lsevents_preregister_event( "%s 0", d->name);
    return d;
}

```

7.5.4.12 `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 1137 of file `lspmac.c`.

```

{
    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;

    pthread_mutex_unlock( &(mp->mutex));

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

```

7.5.4.13 `void lspmac_command_done.cb (char * event)`

Definition at line 4171 of file `lspmac.c`.

```

{
    int i;
    char s[32];
    lspmac_motor_t *mp;
}

```

```

s[0] = 0;
for( i=0; i<sizeof(s)-1 && event[i]; i++) {
    s[i] = 0;
    if( event[i] == ' ' )
        break;
    s[i] = event[i];
}

mp = lspmac_find_motor_by_name( s);

if( mp == NULL)
    return;

pthread_mutex_lock( &(mp->mutex));

mp->command_sent = 1;

pthread_cond_signal( &(mp->cond));
pthread_mutex_unlock( &(mp->mutex));

return;
}

```

7.5.4.14 void lspmac_cryoSwitchChanged_cb(char * event)

Definition at line 3845 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);
}

```

7.5.4.15 lspmac_motor_t* lspmac_dac_init(lspmac_motor_t * d, int * posp, char * mvar, char * name, int (*)(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] unitintialized 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 3610 of file lspmac.c.

```

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

    return d;
}

```

7.5.4.16 void lspmac_dac_read (lspmac_motor_t * mp)

Read a DAC motor position.

Parameters

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

Definition at line 1157 of file lspmac.c.

```

    {
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;
    }
}

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

```

7.5.4.17 void lspmac_Error (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 783 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);
        doupdate();
        pthread_mutex_unlock( &ncurses_mutex);
    }
}
lspmac_Reset();
}

```


7.5.4.18 `int lspmac_est_move_time (double * est_time, int * mmaskp, lspmac_motor_t * mp_1, int jog_1, char * preset_1, double end_point_1, ...)`

Move the motors and estimate the time it'll take to finish the job.

Returns the estimate time and the coordinate system mask to wait for

Parameters

<i>est_time</i>	Returns number of seconds we estimate the move(s) will take
<i>mmaskp</i>	Mask of coordinate systems we are trying to move, excluding jogs. Used to wait for motions to complete
<i>mp_1</i>	Pointer to first motor
<i>jog_1</i>	1 to force a jog, 0 to try a motion program DO NOT MIX JOGS AND MOTION PROGRAMS IN THE SAME COORDINATE SYSTEM!
<i>preset_1</i>	Name of preset we'd like to move to or NULL if <i>end_point_1</i> should be used instead
<i>end_point_1</i>	End point for the first motor. Ignored if <i>preset_1</i> is non null and identifies a valid preset for this motor
...	Perhaps more quads of motors, jog flags, preset names, and end points. End is a NULL motor pointer MUST END ARG LIST WITH NULL

< units to counts

< The total distance we need to go

< Our maximum velocity

< Our maximum acceleration

< Total time for this motor

< coordinate system motion flags

Definition at line 2737 of file lspmac.c.

```

static char axes[] = "XYZUVWABC";
static int qs[9];
static lspmac_combined_move_t motions[32];
char s[256];
int foundone;
int moving_flags;
struct timespec timeout;
int j;
va_list arg_ptr;
lspmac_motor_t *mp;
double ep, maybe_ep;
char *ps;
double
    min_pos,
    max_pos,
    neutral_pos,
    u2c,
    D,
    V,
    A,
    Tt;
int err;
int jog;
int i;
uint32_t m5075;

// reset our coordinate flags and command strings
//
for( i=0; i<32; i++) {
    motions[i].moveme = 0;
}
m5075 = 0;
if( mmaskp != NULL)
    *mmaskp = 0;

//
// Initialize first iteration
//
*est_time = 0.0;

```



```

*      we need to use equation (1) otherwise we need to use equation (2)
*
*/

if( mp->magic != LSPMAC_MAGIC_NUMBER) {
    lslogging_log_message( "lspmac_est_move_time:
        WARNING: bad motor structure. Check that your motor list is NULL terminated.");
    break;
}

lslogging_log_message( "lspmac_est_move_time: find
    motor %s, jog %d, preset %s, endpoint %f",
        mp->name, jog, ps == NULL ? "NULL" : ps, ep);

Tt = 0.0;
if( mp != NULL && mp->max_speed != NULL && mp->max_accel
    != NULL && mp->u2c != NULL) {

    //
    // get the real endpoint if a preset was mentioned
    //
    if( ps != NULL && *ps != 0) {
        err = lsredis_find_preset( mp->name, ps, &
            maybe_ep);
        if( err != 0)
            ep = maybe_ep;
    }

    u2c = lsredis_getd( mp->u2c);

    if( u2c <= 0.0)
        continue;

    //
    // For look up tables user units are (or should be) counts and u2c should
    // be 1
    //
    if( mp->nlut > 0 && mp->lut != NULL) {
        u2c = 1.0;
        D = lspmac_lut( mp->nlut, mp->lut, ep) - lspmac_lut
            ( mp->nlut, mp->lut, lspmac_getPosition( mp));
    } else {
        D = ep - lspmac_getPosition( mp);
    }
    // User units
}

V = lsredis_getd( mp->max_speed) / u2c * 1000.;
// User units per second
A = lsredis_getd( mp->max_accel) / u2c * 1000. *
1000;      // User units per second per second

neutral_pos = lsredis_getd( mp->neutral_pos);
min_pos      = lsredis_getd( mp->min_pos) - neutral_pos
;
max_pos      = lsredis_getd( mp->max_pos) - neutral_pos
;

if( ep < min_pos || ep > max_pos) {
    lslogging_log_message( "lspmac_est_move_time:
        Motor %s Requested position %f out of range: min=%f, max=%f", mp->name, ep,
        min_pos, max_pos);
    lsevents_send_event( "%s Move Aborted", mp->name
    );
    return 1;
}

//
// Don't bother with motors without velocity or acceleration defined
//
if( V > 0.0 && A > 0.0) {
    if( fabs(D) > V*V/A) {
        //
        // Normal ramp up, constant velocity, and ramp down
        //
        Tt = fabs(D)/V + V/A;
    } else {
        //
        // Never reach constant velocity, just ramp up a bit and back down
        //
        Tt = 2.0 * sqrt( fabs(D)/A);
    }

    lslogging_log_message( "lspmac_est_move_time:
        Motor: %s D: %f VV/A: %f Tt: %f", mp->name, D, V*V/A, Tt);
} else {

```

```

//
// TODO: insert move time based for DAC or BO motor like objects;
// For now assume 100 msec;
//
Tt = 0.1;
}

// Perhaps flag a coordinate system
//
// We can move a motor that's not in a coordinate system but we cannot
// move a motor that is but does not
// have an axis defined if we are also moving one that does. It's a
// limitation, I guess.
//
if( jog != 1 &&
    mp->coord_num != NULL && lsredis_getl( mp->
coord_num) > 0 && lsredis_getl( mp->coord_num) <=
16 &&
    mp->motor_num != NULL && lsredis_getl( mp->
motor_num) > 0 && mp->axis != NULL && lsredis_getc( mp
->axis) != 0) {
    int axis;
    int motor_num;

    motor_num = lsredis_getl( mp->motor_num);

    axis = lsredis_getc( mp->axis);
    for( j=0; j<sizeof(axes); j++) {
        if( axis == axes[j])
            break;
    }

    if( j < sizeof( axes)) {
        //
        // Store the motion request for a normal PMAC motor
        //
        int cn;
        int in_position_band;

        cn = lsredis_getl( mp->coord_num);
        in_position_band = lsredis_getl( mp->in_position_band
);

        motions[motor_num - 1].coord_num = cn;
        motions[motor_num - 1].axis = j;
        motions[motor_num - 1].Delta = D * u2c;
        //
        // Don't ask to run a motion program if we are already where we want
        // to be
        //
        // Deadband is 10 counts except for zoom which is 100.
        // We use Ixx28 In-Position Band which has units of 1/16 count
        //
        //
        if( abs(motions[motor_num - 1].Delta)*16 >= in_position_band) {
            m5075 |= (1 << (cn - 1));
            motions[motor_num - 1].moveme = 1;
        }
        lslogging_log_message( "lspmac_est_move_time:
moveme=%d motor '%s' motions index=%d coord_num=%d axis=%d Delta=%d m5075=%u",
                                motions[motor_num-1].moveme, mp->name,
motor_num -1, motions[motor_num-1].coord_num, motions[motor_num-1].axis
, motions[motor_num-1].Delta,
                                m5075);
    }
} else {
    //
    // Here we are dealling with a DAC or BO motor or just want to jog.
    //
    if( mp->jogAbs( mp, ep)) {
        lslogging_log_message( "lspmac_est_move_time:
motor %s failed to queue move of distance %f from %f", mp->name, D,
lspmac_getPosition(mp));
        lsevents_send_event( "Move Aborted");
        return 1;
    }
}
//
// Update the estimated time
//
*est_time = *est_time < Tt ? Tt : *est_time;

lslogging_log_message( "lspmac_est_move_time:
est_time=%f", *est_time);
}

```

```

    mp = va_arg( arg_ptr, lspmac_motor_t *);
    if( mp == NULL)
        break;

    jog = va_arg( arg_ptr, int);
    ps = va_arg( arg_ptr, char *);
    ep = va_arg( arg_ptr, double);

}
va_end( arg_ptr);

// Set the motion program flags
//
if( m5075 != 0) {
    if( mmaskp != NULL)
        *mmaskp |= m5075; // Tell the caller about our new mask

    pthread_mutex_lock( &lspmac_moving_mutex);
    if( (lspmac_moving_flags & m5075) != m5075)
        lspmac_SockSendDPLine( NULL, "M5075=(M5075 | %d)",
            m5075);

    clock_gettime( CLOCK_REALTIME, &timeout);
    //
    timeout.tv_sec += 2; // 2 seconds should be more than enough time to
        set the flags
    err = 0;
    while( err == 0 && (lspmac_moving_flags & m5075) !=
        m5075)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
            lspmac_moving_mutex, &timeout);
    moving_flags = lspmac_moving_flags;
    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "lspmac_est_move_time: Timed
            out waiting for moving flags. lspmac_moving_flags = %0x", moving_flags);
        lsevents_send_event( "Combined Move Aborted");
        return 1;
    }
}

for( i=1; i<=16; i++) {
    //
    // Loop over coordinate systems
    //
    foundone = 0;

    for( j=0; j<9; j++)
        qs[j] = 0;

    for( j=0; j<31; j++) {
        //
        // Loop over motors
        //
        if( motions[j].moveme && motions[j].coord_num == i) {
            if( abs(motions[j].Delta) > 0) {
                qs[(int)(motions[j].axis)] = motions[j].Delta;
                foundone=1;
            }
        }
    }

    if( foundone) {
        sprintf( s, "%d Q40=%d Q41=%d Q42=%d Q43=%d Q44=%d Q45=%d Q46=%d Q47=%d
            Q48=%d Q49=%.1f Q100=%d B180R",
            i, qs[0], qs[1], qs[2], qs[3], qs[4], qs[5], qs[6], qs[7], qs[8]
            , *est_time * 1000., 1 << (i-1));

        lspmac_SockSendDPLine( NULL, s);
    }
}
return 0;
}

```

7.5.4.19 int lspmac_est_move_time_wait(double move_time, int cmask, lspmac_motor_t * mp_1, ...)

wait for motion to stop returns non-zero if the wait timed out

Parameters

<i>move_time</i>	The time out in seconds
<i>cmask</i>	A coordinate system mask to wait for
<i>mp_1</i>	NULL terminated list of individual motors to wait for

Both values are returned from `lspmac_est_move_time`

Definition at line 3084 of file `lspmac.c`.

```

    {
        int err;
        double isecs, fsecs;
        struct timespec timeout;
        va_list arg_ptr;
        lspmac_motor_t *mp;

        clock_gettime( CLOCK_REALTIME, &timeout);
        fsecs = modf( move_time, &isecs);
        timeout.tv_sec += (long)floor(isecs);
        timeout.tv_nsec += (long)floor(fsecs * 1.e9);
        timeout.tv_sec += timeout.tv_nsec / 1000000000;
        timeout.tv_nsec %= 1000000000;

        err = 0;
        pthread_mutex_lock( &lspmac_moving_mutex);
        while( err == 0 && (lspmac_moving_flags & cmask) != 0)
            err = pthread_cond_timedwait( &lspmac_moving_cond, &
                lspmac_moving_mutex, &timeout);
        pthread_mutex_unlock( &lspmac_moving_mutex);

        if( err != 0) {
            if( err == ETIMEDOUT) {
                lslogging_log_message( "
                    lstest_lspmac_est_move_time_wait: timed out waiting %f seconds, cmask = 0x%0x", move_time, cmask);
            }
            lspmac_abort();
            return 1;
        }

        va_start( arg_ptr, mp_1);
        for( mp = mp_1; mp != NULL; mp = va_arg( arg_ptr, lspmac_motor_t
            *)) {
            if( mp->magic != LSPMAC_MAGIC_NUMBER) {
                lslogging_log_message( "lspmac_est_move_time_wait:
                    WARNING: motor list must be NULL terminated. Check your call to
                    lspmac_est_move_time_wait.");
            }

            if( lspmac_moveabs_wait( mp, move_time)) {
                lslogging_log_message( "lspmac_est_move_time_wait:
                    timed out waiting %f seconds for motor %s", move_time, mp->name);
                return 1;
            }
        }
        va_end( arg_ptr);

        return 0;
    }

```

7.5.4.20 `lspmac_motor_t*` `lspmac.find_motor_by_name(char * name)`

Definition at line 4154 of file `lspmac.c`.

```

    {
        lspmac_motor_t *rtn;
        ENTRY entry_in, *entry_outp;
        int err;

        entry_in.key = name;
        entry_in.data = NULL;
        err = hsearch_r( entry_in, FIND, &entry_outp, &motors_ht);
        if( err == 0) {
            lslogging_log_message( "lspmac_find_motor_by_name:
                hsearch_r failed for motor '%s': %s", name, strerror( errno));
            return NULL;
        }
        rtn = entry_outp->data;
    }

```

```

    return rtn;
}

```

7.5.4.21 void lspmac_flight_lut_setup ()

Set up lookup table for flight.

Definition at line 4061 of file lspmac.c.

```

{
    int i;
    lsredis_obj_t *p;

    pthread_mutex_lock( &flight->mutex);

    flight->nlut = 11;
    flight->lut = calloc( 2 * flight->nlut, sizeof( double));
    if( flight->lut == NULL) {
        lslogging_log_message( "lspmac_flight_lut_setup: out
            of memory");
        exit( -1);
    }

    flight->lut[0] = 0;
    flight->lut[1] = 0;
    for( i=1; i < flight->nlut; i++) {
        p = lsredis_get_obj( "cam.zoom.%d.FrontLightIntensity", i);
        if( p==NULL || strlen( lsredis_getstr(p)) == 0) {
            free( flight->lut);
            flight->lut = NULL;
            flight->nlut = 0;
            pthread_mutex_unlock( &flight->mutex);
            lslogging_log_message( "lspmac_flight_lut_setup:
                cannot find MotorPosition element for cam.flight level %d", i);
            return;
        }
        flight->lut[2*i] = i;
        flight->lut[2*i+1] = 32767.0 * lsredis_getd( p) / 100.
            0;
    }
    pthread_mutex_unlock( &flight->mutex);
}

```

7.5.4.22 void lspmac_fscint_lut_setup ()

Set up lookup table for fscint.

Definition at line 4135 of file lspmac.c.

```

{
    int i;

    pthread_mutex_lock( &fscint->mutex);

    fscint->nlut = 101;
    fscint->lut = calloc( 2 * fscint->nlut, sizeof( double));
    if( fscint->lut == NULL) {
        lslogging_log_message( "lspmac_fscint_lut_setup: out
            of memory");
        exit( -1);
    }

    for( i=0; i<fscint->nlut; i++) {
        fscint->lut[2*i] = i;
        fscint->lut[2*i+1] = 320.0 * i;
    }
    pthread_mutex_unlock( &fscint->mutex);
}

```

7.5.4.23 lspmac_motor_t* lspmac_fshut_init(lspmac_motor_t * d)

Inititalize the fast shutter motor.

Parameters

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

Definition at line 3564 of file lspmac.c.

```

{
    _lspmac_motor_init( d, "fastShutter");

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

    return d;
}

```

7.5.4.24 void lspmac_get_ascii (char * event)

Forward declaretion.

Request the ascii buffers from the PMAC.

Definition at line 1954 of file lspmac.c.

```

{
    lspmac_send_command( VR_UPLOAD, VR_PMAC_GETMEM
        , 0x0e9c, 0, sizeof(lspmac_ascii_buffers_t), NULL,
        lspmac_get_ascii_cb, 0, event);
}

```

7.5.4.25 void lspmac_get_ascii.cb (pmac_cmd_queue_t * cmd, int nreceived, char * buff)

service the ascii buffer request response

Definition at line 1846 of file lspmac.c.

```

{
    uint32_t clrdata;
    int need_more;

    need_more = 0;
    pthread_mutex_lock( &lspmac_ascii_mutex);
    memcpy( &lspmac_ascii_buffers, buff, sizeof(
        lspmac_ascii_buffers));

    //
    // The response is not ready yet
    // This will be an infinite loop if we queue a command that does not
    // produce a response.
    //
    // Quoted comments below from Delta Tau "Turbo PMAC User Manual 9/12/2008,
    // page 422"
    //
    // "1. Wait for the Host-Input Control Word at 0x0F40 (Y:$063D0) to become
    // greater than 0, indicating
    // that a response line is ready."
    //
    if( lspmac_ascii_buffers.response_buf == 0) {
        need_more = 1;
    } else {
        if( (lspmac_ascii_buffers.response_buf & 0
            x8000) != 0) {
            char bcd1, bcd2, bcd3;
            int errcode;
            // Error response
            //
            // "2. Interpret the value in this register to determine what
            // type of response is present. If Bit 15 is 1, Turbo PMAC is
            // reporting an error in the command, and there is no response
            // other than this word. In this case, Bits 0 - 11 encode the

```



```

    // error number for the command as 3 BCD digits."
    //
    need_more = 0;
    bcd1 = lspmac_ascii_buffers.response_buf
        & 0x000f;
    bcd2 = (lspmac_ascii_buffers.response_buf
        & 0x00f0) >> 4;
    bcd3 = (lspmac_ascii_buffers.response_buf
        & 0x0f00) >> 8;
    errcode = (bcd3 * 10 + bcd2) * 10 + bcd1;

    if( errcode >= sizeof( pmac_error_strs)/sizeof(
        *pmac_error_strs))
        errcode = 0;
    lslogging_log_message( "lspmac_get_ascii_cb: Error
        returned for %s: %s", lspmac_ascii_buffers.command_str
        , pmac_error_strs[errcode]);
    //
    // Command not allowed during program execution.
    //
    // Requeue it;
    if( errcode == 1) {
        lspmac_dpascii_off--;
    }
} else {
    //
    // "3. Read the response string starting at 0x0F44
    // (Y:$0603D1). Two 8-bit characters are packed into each 16-bit
    // word; the first character is placed into the low
    // byte. Subsequent characters are placed into consecutive
    // higher addresses, two per 16-bit word. (In byte addressing,
    // each character is read from an address one higher than the
    // preceding character.) Up to 255 characters can be sent in a
    // single response line. The string is terminated with the NULL
    // character (byte value 0), convenient for C-style string
    // handling. For Pascal-style string handling, the register at
    // 0x0F42 (X:$0603D0) contains the number of characters in the
    // string (plus one)."
```

```

    //
    if( lspmac_ascii_buffers.response_n > 1)
        lslogging_log_message( "lspmac_get_ascii_cb: '%s'
            '%s'", lspmac_ascii_buffers.command_str,
            lspmac_ascii_buffers.response_str);
    else
        lslogging_log_message( "lspmac_get_ascii_cb: '%s'
            responded", lspmac_ascii_buffers.command_str);

    //
    // 5. "If Bits 0 - 7 of the Host-Input Control Word had
    // contained the value $0D (13 decimal, "CR"), this was not the
    // last line in the response, and steps 1 - 4 should be
    // repeated. If they had contained the value $06 (6 decimal,
    // "ACK"), this was the last line in the response."
    //
    if( (lspmac_ascii_buffers.response_buf &
        0x00ff) == 0x0d) {
        need_more = 1;
    } else {
        need_more = 0;

        if( cmd->event != NULL && *(cmd->event) != 0)
            lsevents_send_event( "%s command accepted", cmd->
                event);
    }
}

pthread_mutex_unlock( &lspmac_ascii_mutex);

//
// Reset the buffer flags and, perhaps, requeue a request
//
// "4. Clear the Host-Input Control Word at 0x0F40 (Y:$063D0)
// to 0. Turbo PMAC will not send another response line until it sees
// this register set to 0."
//
clrdata = 0;          // set the control word to zero

if( need_more) {
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0f40, 0, 4, (char *)&clrdata, lspmac_more_ascii_cb, 1,
        NULL);
} else {
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0f40, 0, 4, (char *)&clrdata, NULL, 1, NULL);
    lspmac_ascii_busy = 0;
}

```

```
}
```

7.5.4.26 void lspmac_get_status ()

Request a status update from the PMAC.

Definition at line 1834 of file lspmac.c.

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

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

Service routing for status upate 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 1610 of file lspmac.c.

```
{
#ifdef SHOW_RATE
static struct timespec ts1;
static struct timespec ts2;
static int cnt = 0;
#endif

int i;
lspmac_bi_t *bp;

clock_gettime( CLOCK_REALTIME, &lspmac_status_time);

#ifdef SHOW_RATE
if( cnt == 0) {
    clock_gettime( CLOCK_REALTIME, &ts1);
}
#endif

pthread_mutex_lock( &md2_status_mutex);
memcpy( &md2_status, buff, sizeof(md2_status));
//
// Note that we are the only thread that writes to md2_status
// so we no longer need the lock to read. Other threads must
// lock the mutex to read 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
    ) {
    int mask;

    lslogging_log_message( "lspmac_get_status_cb: new
        moving flag: %0x", md2_status.moving_flags);
    mask = 1;
    for( i=1; i<=16; i++, mask <<= 1) {
        if( ((lspmac_moving_flags & mask) != 0) && ((
            md2_status.moving_flags & mask) == 0)) {
            // Falling edge: send event
            lsevents_send_event( "Coordsys %d Stopped", i);
        }
    }
    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));

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

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

pthread_mutex_lock( &ncurses_mutex);

// acc11c_1  INPUTS
// mask bit
// 0x01 0 M1000 Air pressure OK
// 0x02 1 M1001 Air bearing OK
// 0x04 2 M1002 Cryo switch
// 0x08 3 M1003 Backlight Down
// 0x10 4 M1004 Backlight Up
// 0x20 5
// 0x40 6 M1006 Cryo is back

//
// acc11c_2  INPUTS
// mask bit
// 0x01 0 M1008 Fluor Dector back
// 0x02 1 M1009 Sample Detected
// 0x04 2 M1020 {SC load request}
// 0x08 3 M1021 {SC move cryo back request}
// 0x10 4 M1022 {SC sample magnet control}
// 0x20 5 M1013 Etel Ready
// 0x40 6 M1014 Etel On
// 0x80 7 M1015 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 Detected");
    else
        mvwprintw( term_status2, 2, 1, "%s", -(LS_DISPLAY_WINDOW_WIDTH
        -2), "Cap Not Detected");
    wnoutrefresh( term_status2);

    // acc11c_3  INPUTS
    // mask  bit
    // 0x01  0   M1025  Minikappa OK
    // 0x02  1   M1023  {SC unload request}
    // 0x04  2   M1024  Smartmagnet is on (note in pmc saying this is not used
    //           in VB interface)
    // 0x08  3   M1027  Arm Parked
    // 0x10  4   M1031  Smartmagnet error (coil is broken)
    // 0x20  5
    // 0x40  6
    // 0x80  7
    // 0x100 8   M1048  Shutter is open (note in pmc says: slow input !!!)

    // acc11c_4  INPUTS
    // mask  bit
    // 0x01  0   M1031  {laser mirror is back}
    // 0x02  1   M1032  {laser PSS OK}
    // 0x04  2   M1033  {laser shutter open}

    // acc11c_5  OUTPUTS
    // mask  bit
    // 0x01  0   M1100  Mag Off
    // 0x02  1   M1191  Condenser Out
    // 0x04  2   M1102  Cryo Back
    // 0x08  3   M1103  Dryer On
    // 0x10  4   M1104  FluoDet Out
    // 0x20  5   M1105  {smartmagnet on/off: note in pmc says this is not used}
    // 0x40  6   M1106  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  OUTPUTS
    // mask  bit
    // 0x0001  0 M1040  {SC Sample transfer is on}
    // 0x0002  1
    // 0x0004  2
    // 0x0008  3
    // 0x0010  4
    // 0x0020  5
    // 0x0040  6
    // 0x0080  7 M1115  Etel Enable
    // 0x0100  8 M1124  Fast Shutter Enable
    // 0x0200  9 M1125  Fast Shutter Manual Enable
    // 0x0400 10 M1126  Fast Shutter On
    // 0x0800 11
    // 0x1000 12 M1128  ADC1 gain bit 0
    // 0x2000 13 M1129  ADC1 gain bit 1
    // 0x4000 14 M1130  ADC2 gain bit 0
    // 0x8000 15 M1131  ADC2 gain bit 1
    //

    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);

#ifdef SHOW_RATE
    if( ++cnt % 1000 == 0) {
        long diff_sec;

```

```

    long diff_nsec;

    clock_gettime( CLOCK_REALTIME, &ts2);

    diff_sec = ts2.tv_sec - ts1.tv_sec;
    diff_nsec = ts2.tv_nsec - ts1.tv_nsec;

    if( diff_nsec < 0 ) {
        diff_nsec += 1000000000;
        diff_sec--;
    }

    lslogging_log_message( "Refresh Rate: %0.1f Hz", (
        double)cnt / (diff_sec + diff_nsec/1000000000.));

    cnt = 0;
}
#endif
}

```

7.5.4.28 void Ispmac.GetAllIVars ()

Request the values of all the I variables.

Definition at line 2066 of file Ispmac.c.

```

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

```

7.5.4.29 void Ispmac.GetAllIVarsCB (pmac_cmd_queue_t * cmd, int nreceived, 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 2049 of file Ispmac.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);
    }
}

```

7.5.4.30 void Ispmac.GetAllMVars ()

Request the values of all the M variables.

Definition at line 2091 of file Ispmac.c.

```

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

```

7.5.4.31 void Ispmac_GetAllMVarsCB (pmac_cmd_queue_t * cmd, int nreceived, 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 2074 of file Ispmac.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);
}
}

```

7.5.4.32 int Ispmac_getBIPosition (Ispmac_bi_t * bip)

get binary input value

Definition at line 1598 of file Ispmac.c.

```

{
int rtn;
pthread_mutex_lock( &bip->mutex);
rtn = bip->position;
pthread_mutex_unlock( &bip->mutex);
return rtn;
}

```

7.5.4.33 void Ispmac_Getmem ()

Request a block of double buffer memory.

Definition at line 1128 of file Ispmac.c.

```

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

```

7.5.4.34 void Ispmac_GetmemReplyCB (pmac_cmd_queue_t * cmd, int nreceived, char * buff)

Service a reply to the getmem command.

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 1054 of file Ispmac.c.

```

{

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

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

```

7.5.4.35 double lspmac_getPosition (lspmac_motor_t * mp)

get the motor position (with locking)

Parameters

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

Definition at line 1355 of file lspmac.c.

```

{

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

```

7.5.4.36 void lspmac_GetShortReplyCB (pmac_cmd_queue_t * cmd, int nreceived, 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 997 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));
}

```

7.5.4.37 void lspmac_home1_queue (lspmac_motor_t * mp)

Home the motor.

Parameters

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

Definition at line 1221 of file lspmac.c.

```

{
    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. TODO (hint hint)
    //
    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) {
                int nogo;
                nogo = 0;
                pthread_mutex_lock( &(lspmac_motors[i].mutex));
                //
                // Don't go on if
                //
                // we are homing          or          ( not in position
                while      in open loop)
                //
                if( lspmac_motors[i].homing || (((lspmac_motors
                    [i].status2 & 0x01)==0) && ((lspmac_motors[i].status1 & 0x040000)
                    != 0)))
                    nogo = 1;
                pthread_mutex_unlock( &(lspmac_motors[i].mutex));
                if( nogo) {
                    pthread_mutex_unlock( &(mp->mutex));
                    return;
                }
            }
        }
    }
    mp->homing = 1;
    mp->not_done = 1; // set up waiting for cond
    mp->motion_seen = 0;
    // 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) {
    lspmac_SockSendDPline( mp->name, "##d$*",
        motor_num);
}

pthread_mutex_unlock( &(mp->mutex));

lsevents_send_event( "%s Homing", mp->name);
}

```

7.5.4.38 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 1309 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_SockSendDPline( mp->name, *spp);
}

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

```

7.5.4.39 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 3671 of file lspmac.c.

```

    {
int i;
int err;
ENTRY entry_in, *entry_outp;
md2_status_t *p;
pthread_mutexattr_t mutex_initializer;

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

// Use recursive mutexs
//
pthread_mutexattr_init( &mutex_initializer);
pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

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

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

//
// 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 X", "omega",
lspmac_moveabs_queue, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, 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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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);

smart_mag_oo = lspmac_bo_init( &(lspmac_motors
[19]), "smartMagnet", "M1100=%d", &(md2_status.acc11c_5), 0x01)
;
blight_ud = lspmac_bo_init( &(lspmac_motors
[20]), "backLight", "M1101=%d", &(md2_status.acc11c_5), 0x02)
;
cryo = lspmac_bo_init( &(lspmac_motors
[21]), "cryo", "M1102=%d", &(md2_status.acc11c_5), 0x04)
;
dryer = lspmac_bo_init( &(lspmac_motors
[22]), "dryer", "M1103=%d", &(md2_status.acc11c_5), 0x08)
;
fluo = lspmac_bo_init( &(lspmac_motors
[23]), "fluo", "M1104=%d", &(md2_status.acc11c_5), 0x10)
;
flight_oo = lspmac_soft_motor_init( &(
lspmac_motors[24]), "frontLight",
lspmac_moveabs_frontlight_oo_queue);
blight_f = lspmac_soft_motor_init( &(
lspmac_motors[25]), "backLight.factor",
lspmac_moveabs_blight_factor_queue);
flight_f = lspmac_soft_motor_init( &(
lspmac_motors[26]), "frontLight.factor",
lspmac_moveabs_flight_factor_queue);

lp_air = lspmac_bi_init( &(lspmac_bis[
0]), &(md2_status.acc11c_1), 0x01, "Low Pressure Air OK", "
Low Pressure Air Failed");
hp_air = lspmac_bi_init( &(lspmac_bis[
1]), &(md2_status.acc11c_1), 0x02, "High Pressure Air OK", "
High Pressure Air Failed");
cryo_switch = lspmac_bi_init( &(lspmac_bis
[ 2]), &(md2_status.acc11c_1), 0x04, "CryoSwitchChanged",
"CryoSwitchChanged");
blight_down = lspmac_bi_init( &(lspmac_bis
[ 3]), &(md2_status.acc11c_1), 0x08, "Backlight Down",
"Backlight Not Down");
blight_up = lspmac_bi_init( &(lspmac_bis
[ 4]), &(md2_status.acc11c_1), 0x10, "Backlight Up",
"Backlight Not Up");
cryo_back = lspmac_bi_init( &(lspmac_bis
[ 5]), &(md2_status.acc11c_1), 0x40, "Cryo Back",
"Cryo Not Back");
fluor_back = lspmac_bi_init( &(lspmac_bis
[ 6]), &(md2_status.acc11c_2), 0x01, "Fluor. Det. Parked",
"Fluor. Det. Not Parked");
sample_detected = lspmac_bi_init( &(lspmac_bis

```

```

    [ 7]), &(md2_status.accl1c_2), 0x02, "SamplePresent",
    "SampleAbsent");
    etel_ready = lspmac_bi_init( &(lspmac_bis
    [ 8]), &(md2_status.accl1c_2), 0x20, "ETEL Ready",
    "ETEL Not Ready");
    etel_on = lspmac_bi_init( &(lspmac_bis
    [ 9]), &(md2_status.accl1c_2), 0x40, "ETEL On",
    "ETEL Off");
    etel_init_ok = lspmac_bi_init( &(lspmac_bis
    [10]), &(md2_status.accl1c_2), 0x80, "ETEL Init OK",
    "ETEL Init Not OK");
    minikappa_ok = lspmac_bi_init( &(lspmac_bis
    [11]), &(md2_status.accl1c_3), 0x01, "Minikappa OK",
    "Minikappa Not OK");
    smart_mag_on = lspmac_bi_init( &(lspmac_bis
    [12]), &(md2_status.accl1c_3), 0x04, "Smart Magnet On",
    "Smart Magnet Not On");
    arm_parked = lspmac_bi_init( &(lspmac_bis
    [13]), &(md2_status.accl1c_3), 0x08, "Arm Parked",
    "Arm Not Parked");
    smart_mag_err = lspmac_bi_init( &(lspmac_bis
    [14]), &(md2_status.accl1c_3), 0x10, "Smart Magnet Error",
    "Smart Magnet OK");
    shutter_open = lspmac_bi_init( &(lspmac_bis
    [15]), &(md2_status.accl1c_3), 0x100, "Shutter Open",
    "Shutter Not Open");
    smart_mag_off = lspmac_bi_init( &(lspmac_bis
    [16]), &(md2_status.accl1c_5), 0x01, "Smart Magnet Off",
    "Smart Magnet Not Off");

// Set up hash table
//
err = hcreate_r( LSPMAC_MAX_MOTORS * 2, &motors_ht)
;
if( err == 0) {
    lslogging_log_message( "lspmac_init: hcreate_r failed:
    '%s'", strerror( errno));
    exit( -1);
}
for( i=0; i<lspmac_nmotors; i++) {
    entry_in.key = lspmac_motors[i].name;
    entry_in.data = &(lspmac_motors[i]);
    err = hsearch_r( entry_in, ENTER, &entry_outp, &motors_ht);
    if( err == 0) {
        lslogging_log_message( "lspmac_init: hsearch_r
        failed for motor %s: '%s'", lspmac_motors[i].name, strerror( errno));
        exit( -1);
    }
}

//
// 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, &mutex_initializer);
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, &
    mutex_initializer);
pthread_cond_init( &lspmac_shutter_cond, NULL);
pmacfd.fd = -1;

pthread_mutex_init( &lspmac_moving_mutex, &
    mutex_initializer);
pthread_cond_init( &lspmac_moving_cond, NULL);

pthread_mutex_init( &lspmac_ascii_mutex, &mutex_initializer
    );

pthread_mutex_init( &lspmac_ascii_buffers_mutex, &
    mutex_initializer);

//
// clear the ascii communications buffers
//
{
    uint32_t cc;
    cc = 0;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);

    cc = 0x18;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);
}

lspmac_SockSendDPLine( NULL, "I5=0");
lspmac_SockSendDPLine( NULL, "ENABLE PLCC 0,2");
lspmac_SockSendDPLine( NULL, "DISABLE PLCC 1");
lspmac_SockSendDPLine( NULL, "I5=3");

lsevents_preregister_event( "omega crossed zero");
lsevents_preregister_event( "Move Aborted");
lsevents_preregister_event( "Combined Move Aborted"
    );

for( i=1; i<=16; i++) {
    lsevents_preregister_event( "Coordsys %d Stopped"
        , i);
}
}

```

7.5.4.40 int 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 3383 of file lspmac.c.

```

{
    return lspmac_move_or_jog_abs_queue( mp,
        requested_position, 1);
}

```

7.5.4.41 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 3929 of file lspmac.c.

```

{
    int z;

    pthread_mutex_lock( &zoom->mutex);
    z = zoom->requested_position;
    pthread_mutex_unlock( &zoom->mutex);

    lslogging_log_message( "lspmac_light_zoom_cb: zoom = %d"
        , z);

    if( lspmac_getPosition( flight_oo) != 0.0) {
        flight->moveAbs( flight, (double)z);
    } else {
        flight->moveAbs( flight, 0.0);
    }
    if( lspmac_getPosition( blight_ud) != 0.0) {
        blight->moveAbs( blight, (double)z);
    } else {
        blight->moveAbs( blight, 0.0);
    }
}

```

7.5.4.42 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

in	<i>nlut</i>	number of entries in lookup table
in	<i>lut</i>	The lookup table: even indicies are the x values, odd are the y's
in	<i>x</i>	The x value we are looking up.

Definition at line 394 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;
}

```

7.5.4.43 void lspmac_more_ascii.cb (pmac_cmd_queue_t * cmd, int nreceived, char * buff)

we are expecting more characters from the DPRAM ASCII interface

Definition at line 1840 of file lspmac.c.

```

{
    lspmac_get_ascii( cmd->event);
}

```

7.5.4.44 lspmac_motor_t* lspmac_motor_init(lspmac_motor_t * d, int wy, int wx, int * posp, int * stat1p, int * stat2p, char * wtitle, char * name, int(*) (lspmac_motor_t *, double) moveAbs, int(*) (lspmac_motor_t *, double) jogAbs)

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 (motion program preferred)
in	<i>jogAbs</i>	Method to use to jog this motor (jog preferred)

Definition at line 3525 of file lspmac.c.

```

{
    _lspmac_motor_init( d, name);

    d->moveAbs      = moveAbs;
    d->jogAbs       = jogAbs;
    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);

    lsevents_preregister_event( "%s Homing", d->

```

```

        name);
    lsevents_preregister_event( "%s Homed",          d->
        name);
    lsevents_preregister_event( "%s Moving",         d->
        name);
    lsevents_preregister_event( "%s In Position",    d->
        name);
    lsevents_preregister_event( "%s Move Aborted",   d->
        name);

    return d;
}

```

7.5.4.45 int 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 Returns non-zero on abort, zero if OK.

< format string for coordinate system move

< 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 3135 of file lspmac.c.

```

{
    char *fmt;
    int ql00;
    int requested_pos_cnts;
    int coord_num, motor_num;
    char *axis;
    double u2c;
    double neutral_pos;
    double min_pos, max_pos;
    int pos_limit_hit, neg_limit_hit, in_position_band;
    struct timespec timeout, now;
    int err;

    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);
    neutral_pos  = lsredis_getd( mp->neutral_pos);
    min_pos      = lsredis_getd( mp->min_pos) -
        neutral_pos;
    max_pos      = lsredis_getd( mp->max_pos) -
        neutral_pos;
    pos_limit_hit = lsredis_getd( mp->pos_limit_hit
    );
    neg_limit_hit = lsredis_getd( mp->neg_limit_hit
    );
    in_position_band = lsredis_getl( mp->in_position_band
    );

    if( u2c == 0.0 || requested_position < min_pos || requested_position >
        max_pos) {
        //
        // Shouldn't try moving a motor that's in trouble
        //
        pthread_mutex_unlock( &(mp->mutex));
        lslogging_log_message( "lspmac_move_or_jog_abs_queue:
            %s u2c=%f requested position=%f min allowed=%f max allowed=%f", mp->name
            , u2c, requested_position, min_pos, max_pos);
    }
}

```



```

    lsevents_send_event( "%s Move Aborted", mp->name);
    return 1;
}

if( (neg_limit_hit && (requested_position < mp->position)) || (pos_limit_hit
    && (requested_position > mp->position))) {
    pthread_mutex_unlock( &(mp->mutex));
    lslogging_log_message( "lspmac_move_or_jog_abs_queue:
        %s Moving wrong way on limit: requested position=%f current position=%f low
        limit=%d high limit=%d",
            mp->name, requested_position, mp->position
            , neg_limit_hit, pos_limit_hit);
    lsevents_send_event( "%s Move Aborted", mp->name);
    return 2;
}

mp->requested_position = requested_position;
if( mp->nlut > 0 && mp->lut != NULL) {
    mp->requested_pos_cnts = lspmac_lut( mp->nlut
        , mp->lut, requested_position);
} else {
    mp->requested_pos_cnts = u2c * (requested_position +
        neutral_pos);
}
requested_pos_cnts = mp->requested_pos_cnts;

//
// Bluff if we are already there
//
if( (abs( requested_pos_cnts - mp->actual_pos_cnts) * 16 <
    in_position_band) || (lsredis_getb( mp->active) != 1)) {
    //
    // Lie and say we moved even though we didn't. Who will know? We are
    // within the deadband or not active.
    //
    mp->not_done = 1;
    mp->motion_seen = 0;
    mp->command_sent = 0;

    lsevents_send_event( "%s Moving", mp->name);

    mp->not_done = 0;
    mp->motion_seen = 1;
    mp->command_sent = 1;

    if( lsredis_getb( mp->active) != 1) {
        //
        // fake the motion for simulated motors
        //
        mp->position = requested_position;
        mp->actual_pos_cnts = requested_pos_cnts;
    }
    pthread_mutex_unlock( &(mp->mutex));

    lsevents_send_event( "%s In Position", mp->name);
    return 0;
}

mp->not_done = 1;
mp->motion_seen = 0;
mp->command_sent = 0;

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) {
    //
    // Make sure the coordinate system is not moving something, wait if it is
    //
    pthread_mutex_lock( &lspmac_moving_mutex);

    clock_gettime( CLOCK_REALTIME, &now);
    //
    // TODO: Have all moves estimate how long they'll take and use that here
    //
    timeout.tv_sec = now.tv_sec + 60.0; // a long timeout, but

```

```

    we might really be moving something that takes this long (or longer)
    timeout.tv_nsec = now.tv_nsec;

    err = 0;
    while( err == 0 && (lspmac_moving_flags & q100) != 0)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
            lspmac_moving_mutex, &timeout);

    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "
            lspmac_move_or_jog_abs_queue: Timed Out.  lspmac_moving_flags = %0x", lspmac_moving_flags
        );
        lsevents_send_event( "%s Move Aborted", mp->name);
        return 1;
    }

    //
    // Set the "we are moving this coordinate system" flag
    //
    lspmac_SockSendDpline( NULL, "M5075=(M5075 | %d)",
        q100);

    switch( *axis) {
    case 'A':
        fmt = "%d Q16=%d Q100=%d B146R";
        break;

    case 'B':
        fmt = "%d Q17=%d Q100=%d B147R";
        break;

    case 'C':
        fmt = "%d Q18=%d Q100=%d B148R";
        break;

    case 'X':
        fmt = "%d Q10=%d Q100=%d B140R";
        break;

    case 'Y':
        fmt = "%d Q11=%d Q100=%d B141R";
        break;

    case 'Z':
        fmt = "%d Q12=%d Q100=%d B142R";
        break;

    case 'U':
        fmt = "%d Q13=%d Q100=%d B143R";
        break;

    case 'V':
        fmt = "%d Q14=%d Q100=%d B144R";
        break;

    case 'W':
        fmt = "%d Q15=%d Q100=%d B145R";
        break;
    }

    //
    // Make sure the flag has been seen
    //

    clock_gettime( CLOCK_REALTIME, &now);
    timeout.tv_sec = now.tv_sec + 4.0; // also a long timeout.
    This should really only take a few milliseconds on a slow day
    timeout.tv_nsec = now.tv_nsec;

    pthread_mutex_lock( &lspmac_moving_mutex);

    err = 0;
    while( err == 0 && (lspmac_moving_flags & q100) == 0)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
            lspmac_moving_mutex, &timeout);
    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "
            lspmac_move_or_jog_abs_queue: Did not see flag propagate.  Move aborted.");
        lsevents_send_event( "%s Move Aborted", mp->name);
        return 1;
    }
}

pthread_mutex_lock( &(mp->mutex));

```

```

if( use_jog ) {
    lspmac_SockSendDpline( mp->name, "#%d j=%d",
        motor_num, requested_pos_cnts);
} else {
    lspmac_SockSendDpline( mp->name, fmt, coord_num,
        requested_pos_cnts, q100);
}
pthread_mutex_unlock( &(mp->mutex));

free( axis);

return 0;
}

```

7.5.4.46 int lspmac_move_or_jog_preset_queue(lspmac_motor_t * mp, char * preset, int use_jog)

move using a preset value returns 0 on success, non-zero on error

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 3344 of file lspmac.c.

```

{
double pos;
int err;
int rtn;

if( preset == NULL || *preset == 0 ) {
    lsevents_send_event( "%s Move Aborted", mp->name);
    return 0;
}

err = lsredis_find_preset( mp->name, preset, &pos);

if( err != 0)
    rtn = lspmac_move_or_jog_abs_queue( mp, pos,
        use_jog);
else {
    lsevents_send_event( "%s Move Aborted", mp->name);
    rtn = 1;
}
return rtn;
}

```

7.5.4.47 int 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>preset_name</i>	Name of the preset to use

Definition at line 2396 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 1;

    err = mp->jogAbs( mp, pos);
    if( !err)
        lslogging_log_message( "lspmac_move_preset_queue:
            moving %s to preset '%s' (%f)", mp->name, preset_name, pos);
    //
    // the abort event should have been sent in moveAbs
    //
    return err;
}

```

7.5.4.48 int lspmac.moveabs_blight_factor_queue (lspmac_motor_t * mp, double pos)

Definition at line 2589 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));
    }

    return 0;
}

```

7.5.4.49 int 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 2470 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;
    lspmac_SockSendDPLine( mp->name, mp->write_fmt
        , mp->requested_pos_cnts);

    pthread_mutex_unlock( &(mp->mutex));
    return 0;
}

```

7.5.4.50 `int lspmac_moveabs_flight_factor_queue (lspmac_motor_t * mp, double pos)`

Definition at line 2566 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));
        return 0;
    }
    return 1;
}

```

7.5.4.51 `int lspmac_moveabs_frontlight_oo_queue (lspmac_motor_t * mp, double pos)`

"move" frontlight on/off

Definition at line 2553 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));
    }
    return 0;
}

```

7.5.4.52 `int 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 2440 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
    //
    lspmac_SockSendDPlane( mp->name, "M1124=0 M1125=1
    M1126=1");
} else {
    //
    // ManualOn=0, ManualEnable=0, ScanEnable=0
    //
    lspmac_SockSendDPlane( mp->name, "M1126=0 M1125=0
    M1124=0");
}

pthread_mutex_unlock( &(mp->mutex));

return 0;
}

```

7.5.4.53 int 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 3372 of file lspmac.c.

```

{
    return lspmac_move_or_jog_abs_queue( mp,
        requested_position, 0);
}

```

7.5.4.54 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 2496 of file lspmac.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
    double u2c;
    double neutral_pos;
    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);
neutral_pos = lsredis_getd( mp->neutral_pos);

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
    + neutral_pos);
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));

pthread_mutex_lock( &(mp->mutex));
lspmac_SockSendDPLine( mp->name, "%d Q10=%d Q11=%d
    Q12=%d Q13=%d Q100=%d B240R", coord_num, q10, q11, q12, q13, q100);
pthread_mutex_unlock( &(mp->mutex));
}

```

7.5.4.55 int lspmac_moveabs_wait(lspmac_motor_t * mp, double timeout_secs)

Wait for motor to finish moving.

Assume motion already queued, now just wait

Parameters

<i>mp</i>	The motor object to wait for
<i>timeout_secs</i>	The number of seconds to wait for. Fractional values fine.

Definition at line 3398 of file lspmac.c.

```

{
    struct timespec timeout, now;
    double isecs, fsecs;
    int err;

    //
    // Copy the queue item for the most recent move request
    //
    clock_gettime( CLOCK_REALTIME, &now);

    fsecs = modf( timeout_secs, &isecs);

    timeout.tv_sec = now.tv_sec + (long)floor( isecs);
    timeout.tv_nsec = now.tv_nsec + (long)floor( fsecs * 1.0e9);

    timeout.tv_sec += timeout.tv_nsec / 1000000000;
    timeout.tv_nsec %= 1000000000;

    err = 0;
    pthread_mutex_lock( &(mp->mutex));

    while( err == 0 && mp->command_sent == 0)
        err = pthread_cond_timedwait( &mp->cond, &mp->mutex, &timeout);
    pthread_mutex_unlock( &(mp->mutex));
    if( err != 0) {
        if( err != ETIMEDOUT) {
            lslogging_log_message( "lspmac_moveabs_wait:
                unexpected error from timedwait %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
                timeout.tv_nsec);
        }
        return 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.

err = 0;
pthread_mutex_lock( &(mp->mutex));
while( err == 0 && mp->motion_seen == 0)
    err = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &timeout)
    ;

if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "lspmac_moveabs_wait:
            unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
            timeout.tv_nsec);
    }
    pthread_mutex_unlock( &(mp->mutex));
    return 1;
}

//
// wait for the motion that we know has started to finish
//
err = 0;
while( err == 0 && mp->not_done)
    err = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &timeout)
    ;

if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "lspmac_moveabs_wait:
            unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
            timeout.tv_nsec);
    }
    pthread_mutex_unlock( &(mp->mutex));
    return 1;
}

//
// 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));
return 0;
}

```

7.5.4.56 int lspmac_movedac.queue (lspmac_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 2309 of file lspmac.c.

```

{
double u2c;

pthread_mutex_lock( &(mp->mutex));

u2c = lsredis_getd( mp->u2c);
mp->requested_position = requested_position;

if( mp->nlut > 0 && mp->lut != NULL) {
    //
    // u2c scales the lookup table value
    //
    mp->requested_pos_cnts = u2c * lspmac_lut( mp->
        nlut, mp->lut, requested_position);

    lslogging_log_message( "lspmac_movedac_queue: motor %s
        requested position %f requested counts %d u2c %f",

```



```

        mp->name, mp->requested_position
    , mp->requested_pos_cnts, u2c);

    mp->not_done    = 1;
    mp->motion_seen = 0;

    lspmac_SockSendDPLine( mp->name, "%s=%d", mp->
        dac_mvar, mp->requested_pos_cnts);
}

pthread_mutex_unlock( &(mp->mutex));
return 0;
}

```

7.5.4.57 int 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 2342 of file lspmac.c.

```

{
    int motor_num;
    int in_position_band;

    lslogging_log_message( "lspmac_movezoom_queue: Here I am
        ");
    pthread_mutex_lock( &(mp->mutex));

    motor_num    = lsredis_getl( mp->motor_num);
    in_position_band = lsredis_getl( mp->in_position_band
        );

    mp->requested_position = requested_position;

    if( mp->nlut > 0 && mp->lut != NULL) {
        mp->requested_pos_cnts = lspmac_lut( mp->nlut
            , mp->lut, requested_position);

        if( abs( mp->requested_pos_cnts - mp->actual_pos_cnts
            ) * 16 <= in_position_band) {
            lslogging_log_message( "lspmac_movezoom_queue:
                Faking move");
            //
            // fake the move
            //
            mp->not_done    = 1;
            mp->motion_seen = 0;
            mp->command_sent = 1;
            pthread_mutex_unlock( &(mp->mutex));

            //
            // Perhaps give someone else a chance to process the move
            //
            pthread_mutex_lock( &(mp->mutex));
            mp->not_done    = 0;
            mp->motion_seen = 1;
            mp->command_sent = 1;
            pthread_mutex_unlock( &(mp->mutex));
            return 0;
        }
    }

    mp->not_done    = 1;
    mp->motion_seen = 0;

    lspmac_SockSendDPLine( mp->name, "##d j=%d",
        motor_num, mp->requested_pos_cnts);
}

pthread_mutex_unlock( &(mp->mutex));
lslogging_log_message( "lspmac_movezoom_queue: There you
    were");
return 0;
}

```

7.5.4.58 void lspmac_next_state ()

State machine logic.

Given the current state, generate the next one

Definition at line 2140 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) {
int goodtogo;
goodtogo = 0;
pthread_mutex_lock( &lspmac_ascii_mutex);
if( lspmac_ascii_busy==0 && lspmac_dpascii_on
!= lspmac_dpascii_off)
goodtogo = 1;
pthread_mutex_unlock( &lspmac_ascii_mutex);
if( goodtogo)
lspmac_SockSendDPqueue();
}

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 states 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 states 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;
}
}

```

7.5.4.59 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 1366 of file lspmac.c.

```

{
    char s[512], *sp;
    int homing1, homing2;
    double u2c;
    double neutral_pos;
    int motor_num;
    char *fmt;
    int status_changed;

    if( lsredis_getb( mp->active) != 1)
        return;

    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 probably 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);
neutral_pos  = lsredis_getd( mp->neutral_pos);

//
// 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_pmacmotor_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
//
if( mp->status1 != *mp->status1_p || mp->status2 != *
    mp->status2_p) {
    mp->status1 = *mp->status1_p;
    mp->status2 = *mp->status2_p;
}

```

```

    status_changed = 1;
} else {
    status_changed = 0;
}
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) -
        neutral_pos);
    } else {
        mp->position = mp->actual_pos_cnts;
    }
}

if( status_changed || fabs(mp->reported_position - mp->
position) >= lsredis_getd(mp->update_resolution
)) {
    fmt = lsredis_getstr(mp->redis_fmt);
    lsredis_setstr( mp->redis_position, fmt, mp->
position);
    free( fmt);
    mp->reported_position = mp->position;
}

fmt = lsredis_getstr( mp->printf_fmt);
snprintf( s, sizeof(s)-1, fmt, 8, mp->position);
s[sizeof(s)-1] = 0;
free( fmt);

//
// indicate limit problems
//
lsredis_setstr( mp->pos_limit_hit, mp->status1
& 0x200000 ? "1" : "0");
lsredis_setstr( mp->neg_limit_hit, mp->status1
& 0x400000 ? "1" : "0");

// 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;
    lsevents_send_event( "%s Homed", mp->name);
}

s[sizeof(s)-1] = 0;
mvwprintw( mp->win, 3, 1, "%s", LS_DISPLAY_WINDOW_WIDTH
-6, s);

if( status_changed) {
    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->status1 & 0x020000)
        sp = "Moving";
    else if( mp->status2 & 0x000001)
        sp = "In Position";

    mvwprintw( mp->win, 6, 1, "%s", LS_DISPLAY_WINDOW_WIDTH
-2, sp);

    lsredis_setstr( mp->status_str, sp);
}
wnoutrefresh( mp->win);

pthread_mutex_unlock( &(mp->mutex));

if( homing1)
    lspmac_home1_queue( mp);

if( homing2)
    lspmac_home2_queue( mp);

lspmac_status_last_time.tv_sec = lspmac_status_time
.tv_sec;
lspmac_status_last_time.tv_nsec = lspmac_status_time
.tv_nsec;
}

```

7.5.4.60 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 refering. Returns the item.

Definition at line 668 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;
}

```

7.5.4.61 `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 688 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;
}

```

7.5.4.62 `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 644 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;
}

```

7.5.4.63 `void` `lspmac_Reset ()`

Clear the queue and put the PMAC into a known state.

Definition at line 767 of file `lspmac.c`.

```

{

```

```

ls_pmac_state = LS_PMAC_STATE_IDLE;

// clear queue
ethCmdReply = ethCmdOn;
ethCmdOff   = ethCmdOn;

lspmac_SockFlush();
}

```

7.5.4.64 void lspmac_reset_queue ()

Clear the queue as part of PMAC reinitialization.

Definition at line 631 of file lspmac.c.

```

{
pthread_mutex_lock( &pmac_queue_mutex);
ethCmdOn   = 0;
ethCmdOff   = 0;
ethCmdReply = 0;
pthread_mutex_unlock( &pmac_queue_mutex);
}

```

7.5.4.65 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 452 of file lspmac.c.

```

{
int i, foundone, up;
double m;
double y1, y2, x1, x2, x;

foundone = 0;
if( lut != NULL && nlut > 1) {

    //
    // are the table values going up or down?
    //
    if( lut[1] < lut[2*nlut-1])
        up = 1;
    else
        up = 0;

    //
    // Linear search
    //
    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];
        }
        //
        // see if y is before the beginning of the table
        //
        if( i==0 && ( up ? y1 > y : y1 < y)) {
            x = x1;
            foundone = 1;
            break;
        }
        //
        // Did we, perhaps, nail it?
        //
        if( y1 == y) {
            x = x1;
            foundone = 1;
            break;
        }
    }
}

```



```

    }

    //
    // Interpolate between the two values (if we've not bumped our heads on
    // the end of the table)
    //
    if( (i < 2*nlut-2) && (up ? y < y2 : y > y2)) {
        m = (x2 - x1) / (y2 - y1);
        x = m * (y - y1) + x1;
        foundone = 1;
        break;
    }
}
//
// y is off the charts: just use the last value
//
if( foundone == 0 ) {
    x = lut[2*(nlut-1)];
}
return x;
}
return 0.0;
}

```

7.5.4.66 void lspmac_run ()

Start up the lspmac thread.

Definition at line 4202 of file lspmac.c.

```

{
    char **inits;
    lspmac_motor_t *mp;
    char evts[64];
    int i;
    int active;
    int motor_num;

    pthread_create( &pmac_thread, NULL, lspmac_worker,
        NULL);

    lsevents_add_listener( "CryoSwitchChanged",
        lspmac_cryoSwitchChanged_cb);
    lsevents_add_listener( "scint In Position",
        lspmac_scint_maybe_turn_on_dryer_cb);
    lsevents_add_listener( "scint Moving",
        lspmac_scint_maybe_turn_off_dryer_cb);
    lsevents_add_listener( "scint In Position",
        lspmac_scint_maybe_return_sample_cb);
    lsevents_add_listener( "scint Moving",
        lspmac_scint_maybe_move_sample_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 Moving",
        lspmac_light_zoom_cb);

    for( i=0; i<lspmac_nmotors; i++) {
        snprintf( evts, sizeof( evts)-1, "%s command accepted", lspmac_motors
            [i].name);
        evts[sizeof( evts)-1] = 0;
        lsevents_add_listener( evts, lspmac_command_done_cb
            );
    }

    lspmac_zoom_lut_setup();
    lspmac_flight_lut_setup();
    lspmac_blight_lut_setup();
    lspmac_fscint_lut_setup();

    //
    // Clear the command interfaces
    //
    lspmac_SockSendControlCharPrint( NULL, '\x18'
        );
    {
        uint32_t cc;
    }
}

```

```

cc = 0;
lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
, 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);

cc = 0x18;
lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
, 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);
}

//
// 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_SockSendDPLine( NULL, *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);
    motor_num = lsredis_getl( mp->motor_num);

    if( motor_num >= 1 && motor_num <= 32) {

        //
        // Set the PMAC to be consistant with redis
        //
        lspmac_SockSendDPLine( NULL, "I%d16=%f I%d17=%f
I%d28=%d", motor_num, lsredis_getd( mp->max_speed), motor_num,
lsredis_getd( mp->max_accel), motor_num, lsredis_getl
( mp->in_position_band));
    }

    // 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->
inactive_init);
        break;

    default:
        lslogging_log_message( "lspmac_run: motor %s is
neither active nor inactive (!?)", mp->name);
        inits = NULL;
    }
    if( inits != NULL) {
        while( *inits != NULL) {
            lspmac_SockSendDPLine( NULL, *inits);
            inits++;
        }
    }
}
}
}

```

7.5.4.67 void lspmac_scint_dried.cb (char * event)

Turn off the dryer.

Parameters

<i>event</i>	required by protocol
--------------	----------------------

Definition at line 4019 of file lspmac.c.

{

```

lslogging_log_message( "lspmac_scint_dried_cb: Stopping
    dryer");
dryer->moveAbs( dryer, 0.0);
}

```

7.5.4.68 void lspmac_scint_maybe_move_sample_cb (char * event)

Perhaps we need to move the sample out of the way.

Definition at line 3953 of file lspmac.c.

```

{
    static int trigger = 0;
    double scint_target;
    int err;
    double move_time;
    int mmask;

    pthread_mutex_lock( &scint->mutex);
    scint_target = scint->requested_position;
    pthread_mutex_unlock( &scint->mutex);

    // This should be pretty conservative since the out position is around 80
    //
    if( scint_target > 10.0) {
        if( trigger) {
            mmask = 0;
            err = lspmac_est_move_time( &move_time, &mmask,
                                       alignx, 0, "Back", -2.0,
                                       aligny, 0, "Back", 1.0,
                                       alignz, 0, "Back", 1.0,
                                       NULL);

            if( err) {
                lspmac_abort();
                lsevents_send_event( "Move Aborted");
                lslogging_log_message( "
lspmac_scint_maybe_move_sample_cb: Failed move request, aborting motion to keep scint from hitting sample"
                );
            }
            trigger = 0;
        }
        else {
            trigger = 1;
        }
    }
}

```

7.5.4.69 void lspmac_scint_maybe_return_sample_cb (char * event)

Perhaps we need to return the sample to the beam.

Definition at line 3988 of file lspmac.c.

```

{
    static int trigger = 0;
    double scint_target;
    double move_time;
    int mmask;

    pthread_mutex_lock( &scint->mutex);
    scint_target = scint->requested_position;
    pthread_mutex_unlock( &scint->mutex);

    // This should be pretty conservative since the out position is around 80
    //
    if( scint_target < 10.0) {
        if( trigger) {
            mmask = 0;
            lspmac_est_move_time( &move_time, &mmask,
                                   alignx, 0, "Beam", 0.0,
                                   aligny, 0, "Beam", 0.0,
                                   alignz, 0, "Beam", 0.0,
                                   NULL);

            trigger = 0;
        }
        else {
            trigger = 1;
        }
    }
}

```

7.5.4.70 void lspmac_scint_maybe_turn_off_dryer_cb (char * event)

Maybe stop drying off the scintillator.

Parameters

<i>event</i>	required by protocol
--------------	----------------------

Definition at line 3895 of file lspmac.c.

```

{
    double pos;

    //
    // See if the dryer is on
    //
    pos = lspmac_getPosition( dryer );

    if( pos == 0.0 )
        return;

    dryer->moveAbs( dryer, 0.0 );

    lstimer_unset_timer( "scintDried" );
}

```

7.5.4.71 void lspmac_scint_maybe_turn_on_dryer_cb (char * event)

Maybe start drying off the scintillator.

Parameters

<i>event</i>	required by protocol
--------------	----------------------

Definition at line 3858 of file lspmac.c.

```

{
    static int trigger = 0;
    double pos;
    double cover;
    int err;

    pthread_mutex_lock( &(amp;scint->mutex) );
    pos = scint->position;
    pthread_mutex_unlock( &(amp;scint->mutex) );

    if( pos > 20.0 ) {
        trigger = 1;
        return;
    }

    if( trigger == 0 ) {
        return;
    }

    err = lsredis_find_preset( scint->name, "Cover",
                              &cover );

    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_set_timer( "scintDried", 1, 120, 0 );
        trigger = 0;
    }
}

```

7.5.4.72 `pmac_cmd_queue_t* lspmac_send_command (int rqType, int rq, int wValue, int wIndex, int wLength, char * data, void(*)(pmac_cmd_queue_t *, int, char *) responseCB, int no_reply, char * event)`

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
in	<i>event</i>	base name for events

Definition at line 706 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;
    cmd.event              = event;

    //
    // 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);
}

```

7.5.4.73 `void lspmac_sendcmd (char * event, void(*)(pmac_cmd_queue_t *, int, char *) responseCB, char * fmt, ...)`

PMAC command with call back.

Parameters

in	<i>event</i>	base name for events
in	<i>responseCB</i>	our callback routine
in	<i>fmt</i>	printf style format string

Definition at line 2119 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_SENDLINE, 0, 0, strlen(tmps), tmps, responseCB, 0,
                             event);
    }

```

7.5.4.74 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 2100 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_SENDLINE, 0, 0, strlen(tmps), tmps, NULL, 0, NULL);
    }

```

7.5.4.75 void lspmac_SendControlReplyPrintCB (pmac_cmd_queue_t * *cmd*, int *nreceived*, 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 1031 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, (unsigned char *)buff);
        pthread_mutex_lock( &ncurses_mutex);
        wnoutrefresh( term_output);
        wnoutrefresh( term_input);
        doupdate();
        pthread_mutex_unlock( &ncurses_mutex);
    }

```

7.5.4.76 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	evt	pollfd object returned by poll
----	-----	--------------------------------

Definition at line 814 of file lspmac.c.

```

    {
static 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
lpmac_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)
            return;

        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) {
        char *newbuff;

        receiveBufferSize += 1400;
        newbuff = calloc( receiveBufferSize, sizeof( unsigned char));
        if( newbuff == NULL) {
            lslogging_log_message( "lspmac_Service: 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;
    }
}
}
}

```

7.5.4.77 int lspmac_set_motion_flags(int *mmaskp, lspmac_motor_t *mp_1, ...)

Set the coordinate system motion flags (m5075) for the null terminated list of motors that we are planning on running a motion program with.

Note that lspmac_est_move_time already takes care of this, use when calling a motion program directly

Parameters

<i>mmaskp</i>	Returned value of the mask generated. Ignored if null.
<i>mp_1</i>	start of null terminated list of motors.

Definition at line 2651 of file lspmac.c.

```

{
    va_list arg_ptr;
    struct timespec timeout;
    int err;
    int cn;
    int need_flag;
    lspmac_motor_t *mp;
    int mmask;

    mmask = 0;
    if( mmaskp != NULL)
        *mmaskp = 0;

    if( mp_1==NULL)
        return 0;

    //
    // add the coordinate system flags to mmask
    //
    va_start( arg_ptr, mp_1);
    for( mp = mp_1; mp!=NULL; mp = va_arg( arg_ptr, lspmac_motor_t
        *)) {
        if( mp->magic != LSPMAC_MAGIC_NUMBER) {
            lslogging_log_message( "lspmac_set_motion_flags:
                WARNING: motor list must be NULL terminated. Check your call to
                lspmac_set_motion_flags.");
            break;
        }
        cn = lsredis_get1( mp->coord_num);
        if( cn < 1 || cn > 16)
            continue;
    }
}

```

```

    mmask |= 1 << (cn - 1);
}
va_end( arg_ptr);

if( mmaskp != NULL)
    *mmaskp = mmask;

//
// It could be the flag is already what we want. We might set up a race
// condition if we
// try to set it again. (so don't)
//
pthread_mutex_lock( &lspmac_moving_mutex);

if( (lspmac_moving_flags & mmask) != 0)
    need_flag = 0;
else
    need_flag = 1;

pthread_mutex_unlock( &lspmac_moving_mutex);

if( !need_flag)
    return 0;

//
// Set m5075 and make sure it propagates
//
lspmac_SockSendDPLine( NULL, "M5075=(M5075 | %d)", mmask
);
clock_gettime( CLOCK_REALTIME, &timeout);
timeout.tv_sec += 2;

err = 0;
pthread_mutex_lock( &lspmac_moving_mutex);
while( err == 0 && (lspmac_moving_flags & mmask) != mmask)
    err = pthread_cond_timedwait( &lspmac_moving_cond, &
        lspmac_moving_mutex, &timeout);

pthread_mutex_unlock( &lspmac_moving_mutex);

if( err == ETIMEDOUT) {
    lslogging_log_message( "lspmac_set_motion_flags: timed
        out waiting for motion %d flag to be set", mmask);
    return 1;
}
return 0;
}

```

7.5.4.78 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	<i>mp</i>	The motor object associated with the fast shutter
----	-----------	---

Definition at line 1187 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;
}

pthread_mutex_unlock( &lspmac_shutter_mutex);
}

```

7.5.4.79 void lspmac.SockFlush ()

Reset the PMAC socket from the PMAC side.

Puts the PMAC into a known communications state

Definition at line 760 of file lspmac.c.

```

{
    lspmac_send_command( VR_DOWNLOAD, VR_PMAC_FLUSH
        , 0, 0, 0, NULL, NULL, 1, NULL);
}

```

7.5.4.80 pmac_cmd_queue_t* lspmac.SockGetmem (int offset, int nbytes)

Request a chunk of memory to be returned.

Parameters

in	<i>offset</i>	Offset in PMAC Double Buffer
in	<i>nbytes</i>	Number of bytes to request

Definition at line 1066 of file lspmac.c.

```

{
    return lspmac_send_command( VR_UPLOAD,
        VR_PMAC_GETMEM, offset, 0, nbytes, NULL, lspmac_GetmemReplyCB
        , 0, NULL);
}

```

7.5.4.81 pmac_cmd_queue_t* lspmac.SockSendControlCharPrint (char * event, char c)

Send a control character.

Parameters

in	<i>event</i>	base name for events
	<i>c</i>	The control character to send

Definition at line 1119 of file lspmac.c.

```

{
    return lspmac_send_command( VR_DOWNLOAD,
        VR_PMAC_SENDCTRLCHAR, c, 0, 0, NULL,
        lspmac_SendControlReplyPrintCB, 0, event);
}

```

7.5.4.82 void lspmac_SockSendDPControlChar (char * event, char c)

use dpram ascii interface to send a control character

Definition at line 1995 of file lspmac.c.

```

{
    uint16_t buff;

    buff = 0x07 & c;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0e9e, 0, 2, (char *)&buff, lspmac_SockSendDPControlCharCB
        , 1, event);
    lsevents_send_event( "%s queued", event);
}

```

7.5.4.83 void lspmac_SockSendDPControlCharCB (pmac_cmd_queue_t * cmd, int nreceived, char * buf)

Definition at line 1988 of file lspmac.c.

```

{
    if( cmd->event != NULL && *(cmd->event))
        lsevents_send_event( "%s accepted", cmd->event);
}

```

7.5.4.84 void lspmac_SockSendDPLine (char * event, char * fmt, ...)

prepare (queue up) a line to send the dpram ascii command interface

Definition at line 1968 of file lspmac.c.

```

{
    va_list arg_ptr;
    uint32_t index;
    char *pl;

    pthread_mutex_lock( &lspmac_ascii_mutex);
    index = lspmac_dpascii_on++ % LSPMAC_DPASCII_QUEUE_LENGTH
        ;

    pl = lspmac_dpascii_queue[index].pl;

    va_start( arg_ptr, fmt);
    vsnprintf( pl, 159, fmt, arg_ptr);
    pl[159] = 0;
    va_end( arg_ptr);

    lspmac_dpascii_queue[index].event = event;

    pthread_mutex_unlock( &lspmac_ascii_mutex);
}

```

7.5.4.85 void lspmac_SockSendDPQueue ()

Definition at line 2004 of file lspmac.c.

```

{
    lspmac_dpascii_queue_t *qp;
    uint32_t mask;
    uint32_t clrdata;

    pthread_mutex_lock( &lspmac_ascii_mutex);
    qp = &(lspmac_dpascii_queue[(lspmac_dpascii_off
        ++)% LSPMAC_DPASCII_QUEUE_LENGTH]);
    lspmac_ascii_busy = 1;
    pthread_mutex_unlock( &lspmac_ascii_mutex);

    lslogging_log_message( "lspmac_SockSendDPQueue: %s", qp

```

```

->p1);

clrdata = 0;           // set the control word to zero
lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
    , 0x0f40, 0, 4, (char *)&clrdata, NULL, 1, NULL);
lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
    , 0x0e9c, 0, 4, (char *)&clrdata, NULL, 1, NULL);

lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
    , 0x0ea0, 0, strlen(qp->p1)+1, qp->p1, NULL, 1, NULL);

mask = 0x0001;
lspmac_send_command( VR_UPLOAD, VR_PMAC_SETBIT
    , 0x0e9c, 1, sizeof( mask), (char *)&mask, lspmac_asciicmdCB, 1,
    qp->event);

if( qp->event != NULL && *(qp->event) != 0)
    lsevents_send_event( "%s queued", qp->event);
}

```

7.5.4.86 `pmac_cmd_queue_t* lspmac_SockSendline (char * event, char * fmt, ...)`

Send a one line command.

Uses printf style arguments.

Parameters

in	<i>event</i>	base name for events
in	<i>fmt</i>	Printf style format string

Definition at line 1076 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, event);
}

```

7.5.4.87 `pmac_cmd_queue_t* lspmac_SockSendline_nr (char * event, char * fmt, ...)`

Send a command and ignore the response.

Parameters

in	<i>event</i>	base name for events
in	<i>fmt</i>	Printf style format string

Definition at line 1099 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_SENDBLINE, 0, 0, strlen( s), s, NULL, 1, event);
}

```

7.5.4.88 `lspmac_motor_t*` `lspmac_soft_motor_init` (`lspmac_motor_t` * *d*, `char` * *name*, `int`(*)(`lspmac_motor_t` *, `double`) *moveAbs*)

Definition at line 3636 of file `lspmac.c`.

```

{

    _lspmac_motor_init( d, name);

    d->moveAbs      = moveAbs;
    d->jogAbs        = moveAbs;
    d->read          = lspmac_soft_motor_read;
    d->actual_pos_cnts_p = calloc( sizeof(int), 1);
    *d->actual_pos_cnts_p = 0;

    return d;
}

```

7.5.4.89 `void` `lspmac_soft_motor_read` (`lspmac_motor_t` * *p*)

Dummy routine to read a soft motor.

Definition at line 3631 of file `lspmac.c`.

```

{

}

```

7.5.4.90 `int` `lspmac_test_preset` (`lspmac_motor_t` * *mp*, `char` * *preset_name*, `double` *tolerance*)

see if the motor is within tolerance of the preset 1 means yes, it is 0 mean no it isn't or that the preset was not found

Definition at line 2419 of file `lspmac.c`.

```

{
    double preset_position;
    int err;

    err = lsredis_find_preset( mp->name, preset_name, &
        preset_position);
    if( err == 0)
        return 0;

    if( fabs( preset_position - lspmac_getPosition( mp)) <=
        tolerance)
        return 1;

    return 0;
}

```

7.5.4.91 `void` `lspmac_video_rotate` (`double` *secs*)

Special motion program to collect centering video.

Definition at line 2613 of file `lspmac.c`.

```

    {
double q10;           // starting position (counts)
double q11;           // delta counts
double q12;           // milliseconds to run over delta

double u2c;
double neutral_pos;

if( secs <= 0.0)
    return;

omega_zero_search = 1;

pthread_mutex_lock( &(omega->mutex));
u2c = lsredis_getd( omega->u2c);
neutral_pos = lsredis_getd( omega->neutral_pos);

q10 = neutral_pos * u2c;
q11 = 360.0 * u2c;
q12 = 1000 * secs;

omega_zero_velocity = 360.0 * u2c / secs; //
    counts/second to back calculate zero crossing time

lspmac_SockSendDPLine( omega->name, "&1
    Q10=%.1f Q11=%.1f Q12=%.1f Q13=(I117) Q14=(I116) B240R", q10, q11, q12);
pthread_mutex_unlock( &(omega->mutex));
}

```

7.5.4.92 void* lspmac_worker(void * dummy)

Our lspmac worker thread.

Parameters

in	<i>dummy</i>	Unused but required by pthread library
----	--------------	--

Definition at line 2258 of file lspmac.c.

```

    {
static int disconnected_notify = 0;
static int old_state;

old_state = ls_pmac_state;
while( 1) {
    int pollrtn;

    lspmac_next_state();

    if( ls_pmac_state != old_state) {
        // lslogging_log_message( "lspmac_worker: state = %d",
        // ls_pmac_state);
        old_state = ls_pmac_state;
    }

    if( pmacfd.fd == -1) {
        if( disconnected_notify == 0)
            lslogging_log_message( "lspmac_worker: PMAC not
            connected");
        disconnected_notify = 1;
        //
        // At this point we assume we became disconnected due to something like a
        // hard boot of the MD2 PMAC
        // and hence the entire system needs reinitialization.
        //
        // It's possible to put in a test here (perhaps using I65) to see if we
        // in fact suffered a reset
        // and need to clear the queue, reinitialize, etc. Or if it was just a
        // networking glitch and do not
        // need to clear the queue and should instead just charge ahead.
        //
        lspmac_reset_queue();
        sleep( 10);
        //
        // This just puts us into a holding pattern until the pmac becomes
        // connected again
        //
        continue;
    }
}

```

```

    }
    disconnected_notify = 0;

    pollrtn = poll( &pmacfd, 1, 10);
    if( pollrtn) {
        lspmac_Service( &pmacfd);
    }
}
}

```

7.5.4.93 void lspmac_zoom_lut_setup ()

Set up lookup table for zoom.

Definition at line 4027 of file lspmac.c.

```

{
    int i;
    lsredis_obj_t *p;
    double neutral_pos;

    neutral_pos = lsredis_getd( zoom->neutral_pos);

    pthread_mutex_lock( &zoom->mutex);

    zoom->nlut = 10;
    zoom->lut = calloc( 2 * zoom->nlut, sizeof( double));
    if( zoom->lut == NULL) {
        lslogging_log_message( "lspmac_zoom_lut_setup: out of
            memory");
        exit( -1);
    }

    for( i=0; i < zoom->nlut; i++) {
        p = lsredis_get_obj( "cam.zoom.%d.MotorPosition", i+1);
        if( p==NULL || strlen( lsredis_getstr(p)) == 0) {
            free( zoom->lut);
            zoom->lut = NULL;
            zoom->nlut = 0;
            pthread_mutex_unlock( &zoom->mutex);
            lslogging_log_message( "lspmac_zoom_lut_setup:
                cannot find MotorPosition element for cam.zoom level %d", i+1);
            return;
        }
        zoom->lut[2*i] = i+1;
        zoom->lut[2*i+1] = lsredis_getd( p) + neutral_pos;
    }
    pthread_mutex_unlock( &zoom->mutex);
}

```

7.5.5 Variable Documentation

7.5.5.1 lspmac_motor_t* alignx

Alignment stage X.

Definition at line 100 of file lspmac.c.

7.5.5.2 lspmac_motor_t* aligny

Alignment stage Y.

Definition at line 101 of file lspmac.c.

7.5.5.3 lspmac_motor_t* alignz

Alignment stage X.

Definition at line 102 of file lspmac.c.

7.5.5.4 Ispmac_motor_t* anal

Polaroid analyzer motor.

Definition at line 103 of file Ispmac.c.

7.5.5.5 Ispmac_motor_t* apery

Aperture Y.

Definition at line 105 of file Ispmac.c.

7.5.5.6 Ispmac_motor_t* aperz

Aperture Z.

Definition at line 106 of file Ispmac.c.

7.5.5.7 Ispmac_bi_t* arm_parked

(whose arm? parked where?)

Definition at line 143 of file Ispmac.c.

7.5.5.8 Ispmac_motor_t* blight

Back Light DAC.

Definition at line 117 of file Ispmac.c.

7.5.5.9 Ispmac_bi_t* blight_down

Backlight is down.

Definition at line 133 of file Ispmac.c.

7.5.5.10 Ispmac_motor_t* blight_f

Back light scale factor.

Definition at line 126 of file Ispmac.c.

7.5.5.11 Ispmac_motor_t* blight_ud

Back light Up/Down actuator.

Definition at line 121 of file Ispmac.c.

7.5.5.12 Ispmac_bi_t* blight_up

Backlight is up.

Definition at line 134 of file Ispmac.c.

7.5.5.13 `lspmac_motor_t* capy`

Capillary Y.

Definition at line 107 of file `lspmac.c`.

7.5.5.14 `lspmac_motor_t* capz`

Capillary Z.

Definition at line 108 of file `lspmac.c`.

7.5.5.15 `lspmac_motor_t* cenx`

Centering Table X.

Definition at line 110 of file `lspmac.c`.

7.5.5.16 `lspmac_motor_t* ceny`

Centering Table Y.

Definition at line 111 of file `lspmac.c`.

7.5.5.17 `pmac_cmd_t cr_cmd` `[static]`

commands to send out "readready", "getbuffer", "controlresponse" (initialized in main)

Definition at line 195 of file `lspmac.c`.

7.5.5.18 `lspmac_motor_t* cryo`

Move the cryostream towards or away from the crystal.

Definition at line 122 of file `lspmac.c`.

7.5.5.19 `lspmac_bi_t* cryo_back`

cryo is in the back position

Definition at line 135 of file `lspmac.c`.

7.5.5.20 `lspmac_bi_t* cryo_switch`

that little toggle switch for the cryo

Definition at line 132 of file `lspmac.c`.

7.5.5.21 `unsigned char dbmem[64 * 1024]` `[static]`

double buffered memory

Definition at line 184 of file `lspmac.c`.

7.5.5.22 `int dbmemIn = 0` `[static]`

next location

Definition at line 185 of file `lspmac.c`.

7.5.5.23 `lspmac_motor_t* dryer`

blow air on the scintillator to dry it off

Definition at line 123 of file `lspmac.c`.

7.5.5.24 `lspmac_bi_t* etel_init_ok`

ETEL initialized OK.

Definition at line 140 of file `lspmac.c`.

7.5.5.25 `lspmac_bi_t* etel_on`

ETEL is on.

Definition at line 139 of file `lspmac.c`.

7.5.5.26 `lspmac_bi_t* etel_ready`

ETEL is ready.

Definition at line 138 of file `lspmac.c`.

7.5.5.27 `unsigned int ethCmdOff = 0` `[static]`

points to current command (or none if == `ethCmdOn`)

Definition at line 198 of file `lspmac.c`.

7.5.5.28 `unsigned int ethCmdOn = 0` `[static]`

points to next empty PMAC command queue position

Definition at line 197 of file `lspmac.c`.

7.5.5.29 `pmac_cmd_queue_t ethCmdQueue[PMAC_CMD_QUEUE_LENGTH]` `[static]`

PMAC command queue.

Definition at line 196 of file `lspmac.c`.

7.5.5.30 `unsigned int ethCmdReply = 0` `[static]`

Used like `ethCmdOff` only to deal with the pmac reply to a command.

Definition at line 199 of file `lspmac.c`.

7.5.5.31 `lspmac_motor_t* flight`

Front Light DAC.

Definition at line 116 of file `lspmac.c`.

7.5.5.32 `lspmac_motor_t* flight_f`

Front light scale factor.

Definition at line 127 of file `lspmac.c`.

7.5.5.33 `lspmac_motor_t* flight.oo`

Turn front light on/off.

Definition at line 125 of file `lspmac.c`.

7.5.5.34 `lspmac_motor_t* fluo`

Move the fluorescence detector in/out.

Definition at line 124 of file `lspmac.c`.

7.5.5.35 `lspmac_bi_t* fluor.back`

fluor is in the back position

Definition at line 136 of file `lspmac.c`.

7.5.5.36 `lspmac_motor_t* fscint`

Scintillator Piezo DAC.

Definition at line 118 of file `lspmac.c`.

7.5.5.37 `lspmac_motor_t* fshut`

Fast shutter.

Definition at line 115 of file `lspmac.c`.

7.5.5.38 `pmac_cmd_t gb.cmd` `[static]`

Definition at line 195 of file `lspmac.c`.

7.5.5.39 `int getivars = 0` `[static]`

flag set at initialization to send i vars to db

Definition at line 88 of file `lspmac.c`.

7.5.5.40 `int getmvars = 0` `[static]`

flag set at initialization to send m vars to db

Definition at line 89 of file lspmac.c.

7.5.5.41 `lspmac_bi_t* hp_air`

High pressure air OK.

Definition at line 131 of file lspmac.c.

7.5.5.42 `lspmac_motor_t* kappa`

Kappa.

Definition at line 112 of file lspmac.c.

7.5.5.43 `lspmac_bi_t* lp_air`

Low pressure air OK.

Definition at line 130 of file lspmac.c.

7.5.5.44 `int ls_pmac.state = LS_PMAC_STATE_DETACHED` `[static]`

Current state of the PMAC communications state machine.

Definition at line 58 of file lspmac.c.

7.5.5.45 `lspmac_ascii_buffers_t lspmac_ascii_buffers` `[static]`

Definition at line 364 of file lspmac.c.

7.5.5.46 `pthread_mutex_t lspmac_ascii_buffers_mutex`

Definition at line 365 of file lspmac.c.

7.5.5.47 `int lspmac_ascii_busy = 0` `[static]`

flag for condition to wait for

Definition at line 75 of file lspmac.c.

7.5.5.48 `pthread_mutex_t lspmac_ascii_mutex` `[static]`

Keep too many processes from sending commands at once.

Definition at line 74 of file lspmac.c.

7.5.5.49 `lspmac_bi_t lspmac_bis[32]`

array of binary inputs

Definition at line 91 of file lspmac.c.

7.5.5.50 `uint32_t lspmac_dpascii_off = 0` `[static]`

Definition at line 375 of file `lspmac.c`.

7.5.5.51 `uint32_t lspmac_dpascii_on = 0` `[static]`

Definition at line 374 of file `lspmac.c`.

7.5.5.52 `lspmac_dpascii_queue_t lspmac_dpascii_queue[LSPMAC_DPASCII_QUEUE_LENGTH]` `[static]`

Definition at line 373 of file `lspmac.c`.

7.5.5.53 `lspmac_motor_t lspmac_motors[LSPMAC_MAX_MOTORS]`

All our motors.

Definition at line 95 of file `lspmac.c`.

7.5.5.54 `pthread_cond_t lspmac_moving_cond`

Wait for motor(s) to finish moving condition.

Definition at line 71 of file `lspmac.c`.

7.5.5.55 `int lspmac_moving_flags`

Flag used to implement motor moving condition.

Definition at line 72 of file `lspmac.c`.

7.5.5.56 `pthread_mutex_t lspmac_moving_mutex`

Coordinate moving motors between threads.

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

7.5.5.57 `int lspmac_nbis = 0`

number of active binary inputs

Definition at line 92 of file `lspmac.c`.

7.5.5.58 `int lspmac_nmotors = 0`

The number of motors we manage.

Definition at line 96 of file `lspmac.c`.

7.5.5.59 `pthread_cond_t lspmac_shutter_cond`

Allows waiting for the shutter status to change.

Definition at line 69 of file `lspmac.c`.

7.5.5.60 `int lspmac_shutter_has_opened`

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

Definition at line 67 of file `lspmac.c`.

7.5.5.61 `pthread_mutex_t lspmac_shutter_mutex`

Coordinates threads reading shutter status.

Definition at line 68 of file `lspmac.c`.

7.5.5.62 `int lspmac_shutter_state`

State of the shutter, used to detect changes.

Definition at line 66 of file `lspmac.c`.

7.5.5.63 `struct timespec lspmac_status_last_time` `[static]`

Time the status was read.

Definition at line 81 of file `lspmac.c`.

7.5.5.64 `struct timespec lspmac_status_time` `[static]`

Time the status was read.

Definition at line 80 of file `lspmac.c`.

7.5.5.65 `md2_status_t md2_status` `[static]`

Buffer for MD2 Status.

Definition at line 350 of file `lspmac.c`.

7.5.5.66 `pthread_mutex_t md2_status_mutex`

Synchronize reading/writing status buffer.

Definition at line 351 of file `lspmac.c`.

7.5.5.67 `lspmac_bi_t* minikappa_ok`

Minikappa is OK (whatever that means)

Definition at line 141 of file `lspmac.c`.

7.5.5.68 `struct hsearch_data motors_ht`

A hash table to find motors by name.

Definition at line 97 of file `lspmac.c`.

7.5.5.69 `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 191 of file `lspmac.c`.

7.5.5.70 `lspmac_motor_t* omega`

MD2 omega axis (the air bearing)

Definition at line 99 of file `lspmac.c`.

7.5.5.71 `int omega_zero_search = 0 [static]`

Indicate we'd really like to know when omega crosses zero.

Definition at line 77 of file `lspmac.c`.

7.5.5.72 `struct timespec omega_zero_time`

Time we believe that omega crossed zero.

Definition at line 79 of file `lspmac.c`.

7.5.5.73 `double omega_zero_velocity = 0 [static]`

rate (cnts/sec) that omega was traveling when it crossed zero

Definition at line 78 of file `lspmac.c`.

7.5.5.74 `lspmac_motor_t* phi`

Phi (not data collection axis)

Definition at line 113 of file `lspmac.c`.

7.5.5.75 `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-chage command while moves stored in CCBUFFER",
  "ERR020: FSAVE issued on Turbo PMAC with incompatible flash memory",
  "ERR021: FSAVE issued while clearing old flash memory sector",
  "ERR022: FREAD attempted but the flash memory is bad"
}
```


Decode the errors perhaps returned by the PMAC.

Definition at line 202 of file lspmac.c.

7.5.5.76 pthread_cond_t pmac_queue_cond

wait for a command to be sent to PMAC before continuing

Definition at line 85 of file lspmac.c.

7.5.5.77 pthread_mutex_t pmac_queue_mutex

manage access to the pmac command queue

Definition at line 84 of file lspmac.c.

7.5.5.78 pthread_t pmac_thread [static]

our thread to manage access and communication to the pmac

Definition at line 83 of file lspmac.c.

7.5.5.79 struct pollfd pmacfd [static]

our poll structure

Definition at line 86 of file lspmac.c.

7.5.5.80 pmac_cmd_t rr_cmd [static]

Definition at line 195 of file lspmac.c.

7.5.5.81 lspmac_bi_t* sample_detected

smart magnet detected sample

Definition at line 137 of file lspmac.c.

7.5.5.82 lspmac_motor_t* scint

Scintillator Z.

Definition at line 109 of file lspmac.c.

7.5.5.83 lspmac_bi_t* shutter_open

shutter is open (note in pmc says this is a slow input)

Definition at line 144 of file lspmac.c.

7.5.5.84 lspmac_bi_t* smart_mag_err

smart magnet error (coil broken perhaps)

Definition at line 145 of file lspmac.c.

7.5.5.85 `lspmac_bi_t*` `smart_mag_off`

smart magnet is off

Definition at line 146 of file `lspmac.c`.

7.5.5.86 `lspmac_bi_t*` `smart_mag_on`

smart magnet is on

Definition at line 142 of file `lspmac.c`.

7.5.5.87 `lspmac_motor_t*` `smart_mag_oo`

Smart Magnet on/off.

Definition at line 120 of file `lspmac.c`.

7.5.5.88 `lspmac_motor_t*` `zoom`

Optical zoom.

Definition at line 104 of file `lspmac.c`.

7.6 `lsredis.c` File Reference

Support redis hash synchronization.

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

Data Structures

- struct [lsredis_preset_list_struct](#)

Typedefs

- typedef struct
[lsredis_preset_list_struct](#) [lsredis_preset_list_t](#)

Functions

- void [lsredis_debugCB](#) ([redisAsyncContext](#) *ac, void *reply, void *privdata)
Log the reply.
- 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 be sure to free the result

- void [lsredis_setstr](#) ([lsredis_obj_t](#) *p, char *fmt,...)
Set the value and update redis.
- double [lsredis_get_or_set_d](#) ([lsredis_obj_t](#) *p, double val, int prec)
- double [lsredis_getd](#) ([lsredis_obj_t](#) *p)
- long int [lsredis_getl](#) ([lsredis_obj_t](#) *p)
- long int [lsredis_get_or_set_l](#) ([lsredis_obj_t](#) *p, long int val)
- 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 Must be called with lsredis_mutex locked.
- [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 mange 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_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.
- void [lsredis_load_presets](#) (char *motor_name)
update the presets hash table for the named motor
- int [lsredis_find_preset](#) (char *motor_name, char *preset_name, double *dval)
Get the value of the given preset and return it in dval Returns 0 on error, non-zero on success;.
- void [lsredis_set_preset](#) (char *motor_name, char *preset_name, double dval)
set the given preset to the given value create a new preset if we can't find it
- int [lsredis_find_preset_index_by_position](#) ([lsrpmac_motor_t](#) *mp)
For the given motor object return the index of the current preset or -1 if we are not at a preset position.
- 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_sig_service](#) (struct pollfd *evt)
- void * [lsredis_worker](#) (void *dummy)
subscribe to changes and service sockets
- void [lsredis_run](#) ()

Variables

- static pthread_t `lsredis_thread`
- pthread_mutex_t `lsredis_mutex` = PTHREAD_RECURSIVE_MUTEX_INITIALIZER_NP
- pthread_cond_t `lsredis_cond`
- int `lsredis_running` = 0
- static `lsredis_obj_t` * `lsredis_objs` = NULL
- static struct hsearch_data `lsredis_htab`
- 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`
- static `lsredis_preset_list_t` * `lsredis_preset_list` = NULL
- static struct hsearch_data `lsredis_preset_ht`
- static int `lsredis_preset_n` = 0
- static int `lsredis_preset_max_n` = 1024
- static pthread_mutex_t `lsredis_preset_list_mutex`

7.6.1 Detailed Description

Support redis hash synchronization.

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

Redis support for redis in pgpmac.

Values in redis are assumed to be hashes with at list one field "VALUE". At startup the initialization routine is passed a regular expression to select which keys we'd like to duplicate locally as a `lsredis_obj_t`. It is assumed that the following construct in redis is used to change a value:

```
MULTI
HSET key VALUE value
PUBLISH publisher key
EXEC
```

Where "publisher" is a unique name in the following format:

```
MD2-*
or    UI-*
or    REDIS_KV_CONNECTOR
or    mk_pgpmac_redis
```

(this last value is used to support the now depreciated px.kvs table in the LS-CAT postgresql server). We assume that all publisher that we are listening to ONLY publish key names that have changed.

When someone else changes a value we invalidate our internal copy and issue a "HGET key VALUE" command. Other threads that request the value of our `lsredis_obj_t` will pause until the new value has been received and processed.

When a value changes locally this module changes it in redis as shown above. At this point we refuse other publishers attempt to change the value until we've seen all of our PUBLISH messages. That is, we ignore changes that in redis happened before our change.

You'll need an `lsredis_obj_t` to do anything with redis in the pgpmac project:

```
lsredis_obj_t *lsredis_get_obj( char *fmt, ...) where fmt is a printf style formatting string
During initialization a "head" string is passed
For example, "omega.position" might refer to t
```

To set a redis value use

```
void lsredis_setstr( lsredis_obj_t *p, char *fmt, ...) where fmt is a printf style formatting
```

When a new value is seen we immediately parse it and make it available through the following functions:

<code>char *lsredis_getstr(lsredis_obj_t *p)</code>	Returns a copy of the VALUE field. Use
<code>double lsredis_getd(lsredis_obj_t *p)</code>	Returns a double. If the value was not
<code>long int lsredis_getl(lsredis_obj_t *p)</code>	Returns a long int. If the value was not
<code>char **lsredis_get_string_array(lsredis_obj_t *p)</code>	Returns an array of string pointers. V or NULL if the value could not be parsed
<code>int lsredis_getb(lsredis_obj_t *p)</code>	Returns 1, 0, or -1 based on the first c
<code>char lsredis_getc(lsredis_obj_t *p)</code>	Returns the first character of VALUE

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

7.6.2 Typedef Documentation

7.6.2.1 typedef struct Lsredis_preset_list_struct Lsredis_preset_list_t

7.6.3 Function Documentation

7.6.3.1 Lsredis_obj_t* Lsredis_get_obj(char * key)

Maybe add a new object Used internally for this module Must be called with Lsredis_mutex locked.

Definition at line 505 of file Lsredis.c.

```

{
    lsredis_obj_t *p;
    regmatch_t pmatch[2];
    int err;
    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;
    }

    // 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) {
    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 (events_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);
    }

    //
    // 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;
}
//
// We arrive here with the valid flag lowered.  Go ahead and request the
// latest value.
//
redisAsyncCommand( roac, lsredis_hgetCB, p, "HGET %s VALUE"
    , key);

return p;
}

```

7.6.3.2 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 163 of file lsredis.c.

```

{
    if( strlen(v) >= (unsigned int) 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);
        }
    }
    strncpy( p->value, v, p->value_length - 1);
    p->value[p->value_length-1] = 0;
    p->dvalue = strtod( p->value, NULL);
    p->lvalue = p->dvalue;

    if( p->avalue != NULL) {
        int i;
        for( i=0; (p->avalue)[i] != NULL; i++)
            free( (p->avalue)[i]);
        free( p->avalue);
        p->avalue = NULL;
    }

    p->avalue = lspg_array2ptrs( p->value);

    switch( *(p->value)) {
        case 'T':
        case 't':
        case 'Y':
        case 'y':
        case 'l':
            p->bvalue = 1;
            break;

        case 'F':
        case 'f':
        case 'N':
        case 'n':
        case '0':
            p->bvalue = 0;
            break;

        default:
            p->bvalue = -1;           // nil is -1 here in our world
    }

    p->cvalue = *(p->value);

    if( !(p->valid)) {
        p->valid = 1;
        lsevents_send_event( "%s Valid", p->events_name
            );
    }
}

```

7.6.3.3 void Isredis.addRead (void * data)

hook to mange read events

Definition at line 635 of file Isredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;

    if( (pfd->events & POLLIN) == 0) {
        pfd->events |= POLLIN;
        pthread_kill( lsredis_thread, SIGUSR1);
    }
}

```

7.6.3.4 void Isredis.addWrite (void * data)

hook to manage write events

Definition at line 659 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;

    if( (pfd->events & POLLOUT) == 0) {
        pfd->events |= POLLOUT;
        pthread_kill( lsredis_thread, SIGUSR1);
    }
}

```

7.6.3.5 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 684 of file lsredis.c.

```

{
    struct pollfd *pfd;
    pfd = (struct pollfd *)data;

    pfd->fd = -1;

    if( (pfd->events & (POLLOUT | POLLIN)) != 0) {
        pfd->events &= ~(POLLOUT | POLLIN);
        pthread_kill( lsredis_thread, SIGUSR1);
    }
}

```

7.6.3.6 int lsredis_cmpnstr (lsredis_obj_t * p, char * s, int n)

Definition at line 253 of file lsredis.c.

```

{
    int rtn;
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = strncmp( p->value, s, n);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```

7.6.3.7 int lsredis_cmpstr (lsredis_obj_t * p, char * s)

Definition at line 242 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;
}

```

7.6.3.8 void lsredis_debugCB (redisAsyncContext * ac, void * reply, void * privdata)

Log the reply.

Definition at line 113 of file lsredis.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<(int)r->elements; i++)
        lsredis_debugCB( ac, r->element[i], NULL);
    indentlevel--;
    break;

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

```

7.6.3.9 void Lsredis_delRead (void * data)

hook to manage "don't need to read" events

Definition at line 647 of file Lsredis.c.

```

struct pollfd *pfd;
pfd = (struct pollfd *)data;

if( (pfd->events & POLLIN) != 0) {
    pfd->events &= ~POLLIN;
    pthread_kill( lsredis_thread, SIGUSR1);
}
}

```

7.6.3.10 void Lsredis_delWrite (void * data)

hook to manage "don't need to write anymore" events

Definition at line 671 of file Lsredis.c.

```

{

```

```

struct pollfd *pfd;
pfd = (struct pollfd *)data;

if( (pfd->events & POLLOUT) != 0) {
    pfd->events &= ~POLLOUT;
    pthread_kill( lsredis_thread, SIGUSR1);
}
}

```

7.6.3.11 void lsredis_fd_service (struct pollfd * evt)

service the socket requests

Definition at line 1094 of file lsredis.c.

```

{
    pthread_mutex_lock( &lsredis_mutex);
    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);
    }
    pthread_mutex_unlock( &lsredis_mutex);
}

```

7.6.3.12 int lsredis_find_preset (char * motor_name, char * preset_name, double * dval)

Get the value of the given preset and return it in dval Returns 0 on error, non-zero on success;.

Definition at line 898 of file lsredis.c.

```

{
    char s[512];
    int err;
    ENTRY entry_in, *entry_outp;
    lsredis_preset_list_t *pl;

    snprintf( s, sizeof( s)-1, "%s%s", motor_name, preset_name);
    s[sizeof(s)-1] = 0;

    entry_in.key = s;
    entry_in.data = NULL;
    err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
    );

    if( err == 0) {
        // not found (or some other problem that means we don't have an answer
        //
        // Maybe someone added a new preset and we don't know about it yet
        //
        lsredis_load_presets( motor_name);
        err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
        );
        if( err == 0) {
            //
            // Guess not. Give up. We tried
            //
            *dval = 0.0;
            return 0;
        }
    }
    pl = entry_outp->data;
    *dval = lsredis_getd( pl->position);
    return 1;
}

```

7.6.3.13 `int lsredis_find_preset_index_by_position (lspmac_motor_t * mp)`

For the given motor object return the index of the current preset or -1 if we are not at a preset position.

Definition at line 980 of file lsredis.c.

```

{
    lsredis_obj_t *p;
    int plength;
    int i;
    double ur, pos;

    p = lsredis_get_obj( "%s.presets.length", mp->name);
    plength = lsredis_get_or_set_l( p, 0);

    if( plength <= 0) {
        return -1;
    }

    ur = lsredis_getd( mp->update_resolution);
    pos = lspmac_getPosition( mp);

    for( i=0; i<plength; i++) {
        p = lsredis_get_obj( "%s.presets.%d.position", mp->name,
            i);
        if( fabs( pos - lsredis_getd( p)) <= ur) {
            return i;
        }
    }
    return -1;
}

```

7.6.3.14 `lsredis_obj_t* lsredis_get_obj(char * fmt, ...)`

Definition at line 591 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;

    pthread_mutex_lock( &lsredis_mutex);
    while( lsredis_running == 0)
        pthread_cond_wait( &lsredis_cond, &lsredis_mutex);

    rtn = _lsredis_get_obj( kp);
    pthread_mutex_unlock( &lsredis_mutex);

    free( kp);
    return rtn;
}

```

7.6.3.15 `double lsredis_get_or_set.d (lsredis_obj_t * p, double val, int prec)`

Definition at line 357 of file lsredis.c.

```

long int rtn;
int err;
struct timespec timeout;

clock_gettime( CLOCK_REALTIME, &timeout);
timeout.tv_sec += 2;

pthread_mutex_lock( &p->mutex);
err = 0;
while( err == 0 && p->valid == 0)
    err = pthread_cond_timedwait( &p->cond, &p->mutex, &timeout);

if( err == ETIMEDOUT) {
    rtn = val;
    lsredis_setstr( p, "%.f", prec, val);
} else {
    rtn = p->lvalue;
}
pthread_mutex_unlock( &p->mutex);

return rtn;
}

```

7.6.3.16 long int lsredis_get_or_set_l(lsredis_obj_t *p, long int val)

Definition at line 407 of file lsredis.c.

```

long int rtn;
int err;
struct timespec timeout;

clock_gettime( CLOCK_REALTIME, &timeout);
timeout.tv_sec += 2;

pthread_mutex_lock( &p->mutex);
err = 0;
while( err == 0 && p->valid == 0)
    err = pthread_cond_timedwait( &p->cond, &p->mutex, &timeout);

if( err == ETIMEDOUT) {
    lslogging_log_message( "lsredis_get_or_set_l: using
        default value of %ld for redis variable %s", val, p->key);
    rtn = val;
    lsredis_setstr( p, "%ld", val);
} else {
    rtn = p->lvalue;
}
pthread_mutex_unlock( &p->mutex);

return rtn;
}

```

7.6.3.17 char** lsredis_get_string_array(lsredis_obj_t *p)

Definition at line 432 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;
}

```

7.6.3.18 int lsredis_getb(lsredis_obj_t *p)

Definition at line 445 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;
    }

```

7.6.3.19 char Isredis_getc (Isredis_obj_t * p)

Definition at line 458 of file Isredis.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;
    }

```

7.6.3.20 double Isredis_getd (Isredis_obj_t * p)

Definition at line 381 of file Isredis.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;
    }

```

7.6.3.21 long int Isredis_getl (Isredis_obj_t * p)

Definition at line 394 of file Isredis.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;
    }

```

7.6.3.22 char* Isredis_getstr (Isredis_obj_t * p)

return a copy of the key's string value be sure to free the result

Definition at line 281 of file Isredis.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;
    }

```

7.6.3.23 void lsredis.hgetCB (redisAsyncContext * ac, void * reply, void * privdata)

Definition at line 471 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);
        }
    }

```

7.6.3.24 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 1012 of file lsredis.c.

```

    {
        int err;
        int nerrmsg;
        char *errmsg;

        //
        // set up hash map to store redis objects
        //
        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_cond_init( &lsredis_cond, 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);
wrac = redisAsyncConnect("127.0.0.1", 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;

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);
    }
}

hcreate_r( lsredis_preset_max_n * 2, &lsredis_preset_ht
    );
pthread_mutex_init( &lsredis_preset_list_mutex, NULL
    );
}

```

7.6.3.25 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 802 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< (int)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);
    }
}
}

```

7.6.3.26 void lsredis_load_presets (char * motor_name)

update the presets hash table for the named motor

Definition at line 825 of file lsredis.c.

```

{
lsredis_obj_t *p;
lsredis_preset_list_t *pl;
int plength;
char *preset_name;
int i;
int key_length;
ENTRY entry_in, *entry_outp;

p = lsredis_get_obj( "%s.presets.length", motor_name);
plength = lsredis_get_or_set_l( p, 0);
if( plength <= 0)
    return;

pthread_mutex_lock( &lsredis_preset_list_mutex);

for( i=0; i<plength; i++) {
    pl = calloc( 1, sizeof( lsredis_preset_list_t));
    pl->name = lsredis_get_obj( "%s.presets.%d.name",
        motor_name, i);
    pl->position = lsredis_get_obj( "
        %s.presets.%d.position", motor_name, i);
    pl->index = i;

    preset_name = lsredis_getstr( pl->name);
    key_length = strlen( motor_name) + strlen( preset_name) + 1;
    pl->key = calloc( key_length, 1);

    pl->next = lsredis_preset_list;
    lsredis_preset_list = pl;

    snprintf( pl->key, key_length, "%s%s", motor_name, preset_name);

    entry_in.key = pl->key;
    entry_in.data = pl;
    hsearch_r( entry_in, ENTER, &entry_outp, &lsredis_preset_ht
    );
    if( entry_outp->data != pl) {
        //
        // The key was already there or we couldn't add it
        //
        if( entry_outp->data == NULL)
            lslogging_log_message( "lsredis_load_presets:
                could not add preset '%s' for motor '%s'", preset_name, motor_name);

        free( pl->key);
        free( pl);
    } else {
        //
        // We've successfully added the new key
        //
        lsredis_preset_n++;
        //
    }
}

```



```

// Resize the hash table if we are starting to fill it up
// Generally we prefer a sparse table
//
if( lsredis_preset_n >= lsredis_preset_max_n
) {
    lslogging_log_message( "lsredis_load_presets:
increasing preset hash table size. max now %d", lsredis_preset_max_n
);
    hdestroy_r( &lsredis_preset_ht);
    lsredis_preset_max_n *= 2;
    hcreate_r( 2 * lsredis_preset_max_n, &
lsredis_preset_ht);
    for( pl = lsredis_preset_list; pl != NULL; pl = pl->
next) {
        entry_in.key = pl->key;
        entry_in.data = pl;
        hsearch_r( entry_in, ENTER, &entry_outp, &lsredis_preset_ht
);
    }
    lslogging_log_message( "lsredis_load_presets: done
increasing preset hash table size.", lsredis_preset_max_n);
}
}
free( preset_name);
}
pthread_mutex_unlock( &lsredis_preset_list_mutex);
}

```

7.6.3.27 void lsredis_maybe_add_key(char * k)

Definition at line 794 of file Lsredis.c.

```

{
if( regexec( &lsredis_key_select_regex, k, 0, NULL, 0
) == 0) {
    _lsredis_get_obj( k);
}
}

```

7.6.3.28 int lsredis_regexec(const regex_t * preg, lsredis_obj_t * p, size_t nmatch, regmatch_t * pmatch, int eflags)

Definition at line 264 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);

return rtn;
}

```

7.6.3.29 void lsredis_run()

Definition at line 1219 of file Lsredis.c.

```

{
pthread_create( &lsredis_thread, NULL, lsredis_worker
, NULL);
}

```

7.6.3.30 void lsredis_set_preset (char * motor_name, char * preset_name, double dval)

set the given preset to the given value create a new preset if we can't find it

Definition at line 935 of file lsredis.c.

```

char s[512];
int plength;
int err;
ENTRY entry_in, *entry_outp;
lsredis_obj_t *p, *presets_length_p;
lsredis_preset_list_t *pl;

snprintf( s, sizeof( s)-1, "%s%s", motor_name, preset_name);
s[sizeof(s)-1] = 0;

entry_in.key = s;
entry_in.data = NULL;
err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
);
if( err != 0 ) {
    //
    // Found it. Things are simple.
    //
    pl = entry_outp->data;
    lsredis_setstr( pl->position, "%.3f", dval);
    return;
}
//
// OK, our preset was not found, add it
//
presets_length_p = lsredis_get_obj( "%s.presets.length",
    motor_name);
plength = lsredis_get_or_set_l( presets_length_p, 0);
plength += 1;

snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.name", lsredis_head,
    motor_name, plength-1);
s[sizeof(s)-1] = 0;

p = lsredis_get_obj( "%s.presets.%d.name", motor_name, plength
-1);
lsredis_setstr( p, "%s", preset_name);

p = lsredis_get_obj( "%s.presets.%d.position", motor_name,
    plength-1);
lsredis_setstr( p, "%.3f", dval);

lsredis_setstr( presets_length_p, "%ld", plength);

lsredis_load_presets( motor_name);
}

```

7.6.3.31 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 224 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);
}

```

7.6.3.32 void Isredis_setstr (Isredis_obj_t * p, char * fmt, ...)

Set the value and update redis.

Note that Isredis_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. < up the count of times we need to see ourselves published before we start listening to others again

< Unlock to prevent deadlock in case the service routine needs to set our value

< redisAsyncCommandArgv shouldn't need to access this after it's made up its packet (before it returns) so we should be OK with this location disappearing soon.

Definition at line 306 of file Isredis.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);

    //
    // Don't send an update if a good value has not changed
    //
    if( p->valid && strcmp( v, p->value) == 0) {
        // nothing to do
        pthread_mutex_unlock( &p->mutex);
        return;
    }

    p->wait_for_me++;
    pthread_mutex_unlock( &p->mutex);

    argv[0] = "HSET";
    argv[1] = p->key;
    argv[2] = "VALUE";
    argv[3] = v;

    pthread_mutex_lock( &lsredis_mutex);
    while( lsredis_running == 0)
        pthread_cond_wait( &lsredis_cond, &lsredis_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_mutex);

    // Assume redis will take exactly the value we sent it
    //
    pthread_mutex_lock( &p->mutex);
    _lsredis_set_value( p, v);
    pthread_cond_signal( &p->cond);
    pthread_mutex_unlock( &p->mutex);
}

```

7.6.3.33 void Isredis_sig_service (struct pollfd * evt)

Parameters

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

Definition at line 1118 of file Isredis.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.
        //

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

```

7.6.3.34 void lsredis_subCB (redisAsyncContext * ac, void * reply, void * privdata)

Use the publication to request the new value.

Definition at line 702 of file lsredis.c.

```

{
    redisReply *r;
    lsredis_obj_t *p;
    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( regexexec( &lsredis_key_select_regex, k, 0, NULL, 0
        ) == 0) {
        //
        // We should know about this one
        //

        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;

        if( p == NULL) {
            _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;
    lsevents_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.
    //
    redisAsyncCommand( roac, lsredis_hgetCB, p, "HGET %s
    VALUE", k);
}
}
}

```

7.6.3.35 void* lsredis_worker (void * dummy)

subscribe to changes and service sockets

< poll timeout, in millisecs (of course)

< array of pollfd's for the poll function, one entry per connection

< number of active elements in fda

Definition at line 1137 of file Lsredis.c.

```

{
    static int poll_timeout_ms = -1;
    static struct pollfd fda[4];
    static int nfda = 0;
    static sigset_t our_sigset;
    int pollrtn;
    int i;

    pthread_mutex_lock( &lsredis_mutex);
    //
    // block ordinary signal mechanism
    //
    sigemptyset( &our_sigset);
    sigaddset( &our_sigset, SIGUSR1);
    pthread_sigmask( SIG_BLOCK, &our_sigset, NULL);

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

        es = strerror( errno);
        lslogging_log_message( "lsredis_worker: Signalfd
        trouble '%s'", es);
    }
    fda[0].events = POLLIN;
    nfda = 1;

    lsredis_running = 1;
}

```

```

if( redisAsyncCommand( subac, lsredis_subCB, NULL, "
    PSUBSCRIBE REDIS_KV_CONNECTOR mk_pgpmac_redis UI* MD2-*") == REDIS_ERR) {
    lslogging_log_message( "Error sending PSUBSCRIBE
        command");
}

redisAsyncCommand( roac, lsredis_keysCB, NULL, "KEYS *");
pthread_cond_signal( &lsredis_cond);
pthread_mutex_unlock( &lsredis_mutex);

while(1) {
    nfda = 1;

    pthread_mutex_lock( &lsredis_mutex);
    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++;
    }
    pthread_mutex_unlock( &lsredis_mutex);

    pollrtn = poll( fda, nfda, poll_timeout_ms);

    if( pollrtn && fda[0].revents) {
        lsredis_sig_service( &(fda[0]));
        pollrtn--;
    }

    for( i=1; i<nfda; i++) {
        if( fda[i].revents) {
            lsredis_fd_service( &(fda[i]));
        }
    }
}
}

```

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

call back in case a redis server becomes disconnected TODO: reconnect

Definition at line 627 of file lsredis.c.

```

{
if( status != REDIS_OK) {
    lslogging_log_message( "lsredis: Disconnected with
        status %d", status);
}
}

```

7.6.4 Variable Documentation

7.6.4.1 pthread_cond_t lsredis_cond

Definition at line 75 of file lsredis.c.

7.6.4.2 char* lsredis_head = NULL [static]

Definition at line 88 of file lsredis.c.

7.6.4.3 `struct hsearch_data lsredis_hstab` `[static]`

Definition at line 80 of file lsredis.c.

7.6.4.4 `regex_t lsredis_key_select_regex` `[static]`

Definition at line 87 of file lsredis.c.

7.6.4.5 `pthread_mutex_t lsredis_mutex = PTHREAD_RECURSIVE_MUTEX_INITIALIZER_NP`

Definition at line 74 of file lsredis.c.

7.6.4.6 `lsredis_obj_t* lsredis_objs = NULL` `[static]`

Definition at line 79 of file lsredis.c.

7.6.4.7 `struct hsearch_data lsredis_preset_ht` `[static]`

Definition at line 103 of file lsredis.c.

7.6.4.8 `lsredis_preset_list_t* lsredis_preset_list = NULL` `[static]`

Definition at line 102 of file lsredis.c.

7.6.4.9 `pthread_mutex_t lsredis_preset_list_mutex` `[static]`

Definition at line 106 of file lsredis.c.

7.6.4.10 `int lsredis_preset_max_n = 1024` `[static]`

Definition at line 105 of file lsredis.c.

7.6.4.11 `int lsredis_preset_n = 0` `[static]`

Definition at line 104 of file lsredis.c.

7.6.4.12 `char* lsredis_publisher = NULL` `[static]`

Definition at line 86 of file lsredis.c.

7.6.4.13 `int lsredis_running = 0`

Definition at line 76 of file lsredis.c.

7.6.4.14 `pthread_t lsredis_thread` `[static]`

Definition at line 72 of file lsredis.c.

7.6.4.15 `redisAsyncContext* roac` `[static]`

Definition at line 83 of file `lsredis.c`.

7.6.4.16 `struct pollfd rofd` `[static]`

Definition at line 91 of file `lsredis.c`.

7.6.4.17 `redisAsyncContext* subac` `[static]`

Definition at line 82 of file `lsredis.c`.

7.6.4.18 `struct pollfd subfd` `[static]`

Definition at line 90 of file `lsredis.c`.

7.6.4.19 `redisAsyncContext* wrac` `[static]`

Definition at line 84 of file `lsredis.c`.

7.6.4.20 `struct pollfd wrfd` `[static]`

Definition at line 92 of file `lsredis.c`.

7.7 `lstest.c` File Reference

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

Functions

- void [lstest_lspmac_est_move_time](#) ()
- void [lstest_main](#) ()

7.7.1 Function Documentation

7.7.1.1 `void lstest_lspmac_est_move_time ()`

Definition at line 14 of file `lstest.c`.

```

{
    int err;
    double move_time;
    double fudge;
    int mmask;

    fudge = 2.0;

    mmask = 0;
    err = lspmac_est_move_time( &move_time, &mmask, omega
        , 0, NULL, 360., NULL);
    lslogging_log_message( "lstest_lspmac_est_move_time:
        omega 360 move_time=%f err=%d", move_time, err);

    if( lspmac_est_move_time_wait( move_time + fudge,
        mmask, NULL)) {

```



```

    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, aperz
    , 0, "Cover", 0., NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    aperz Cover move_time=%f err=%d", move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, aperz
    , 0, "In", 0., NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    aperz In move_time=%f err=%d", move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, capz,
    0, "Cover", 0., NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    capz Cover move_time=%f err=%d", move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, capz,
    0, "In", 0., NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    capz In move_time=%f err=%d", move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, apery
    , 0, "In", 0.0, aperz, 0, "In", 0.0, capy, 0, "In", 0.0, capz, 0, "
    In", 0.0, scint, 0, "Scintillator", 0.0, NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    apery In aperz In capy In capz In scint Scintillator move_time=%f err=%d",
    move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, apery
    , 0, "In", 0.0, aperz, 0, "Cover", 0.0, capy, 0, "In", 0.0, capz, 0
    , "Cover", 0.0, scint, 0, "Cover", 0.0, NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:
    apery Cover aperz Cover capy Cover capz Cover scint Cover move_time=%f err=%d",
    move_time, err);

if( lspmac_est_move_time_wait( move_time + fudge,
    mmask, NULL)) {
    lslogging_log_message( "ltest_lspmac_est_move_time:
        timed out");
    return;
}

err = lspmac_est_move_time( &move_time, &mmask, apery
    , 1, "In", 0.0, aperz, 1, "In", 0.0, capz, 1, "In", 0.0, capz, 1, "
    In", 0.0, scint, 1, "Scintillator", 0.0,
        omega, 0, "manualMount", 0.0, kappa, 0,
        "manualMount", 0.0, NULL);
lslogging_log_message( "ltest_lspmac_est_move_time:

```

```

    apery In aperz In capy In capz In scint Scintillator omega manualMount kappa
    Manualmount move_time=%f err=%d", move_time, err);

    if( lspmac_est_move_time_wait( move_time + fudge,
        mmask, NULL)) {
        lslogging_log_message( "lptest_lspmac_est_move_time:
            timed out");
        return;
    }
}

```

7.7.1.2 void lptest_main ()

Definition at line 92 of file lptest.c.

```

    {
        lptest_lspmac_est_move_time();
    }

```

7.8 Lstimer.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_unset_timer](#) (char *event)
Unsets all timers for the given event.
- void [lstimer_set_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 * [ltimer_worker](#) (void *dummy)

Our worker.

- void [ltimer_init](#) ()

Initialize the timer list and pthread stuff.

- void [ltimer_run](#) ()

Start up our thread.

Variables

- static int [ltimer_active_timers](#) = 0

count of the number timers we are tracking

- static [ltimer_list_t](#) [ltimer_list](#) [[LSTIMER_LIST_LENGTH](#)]

Our timer list.

- static pthread_t [ltimer_thread](#)

the timer thread

- static pthread_mutex_t [ltimer_mutex](#)

protect the timer list

- static pthread_cond_t [ltimer_cond](#)

allows us to be idle when there is nothing to do

- static timer_t [ltimer_timerid](#)

our real time timer

- static int [new_timer](#) = 0

indicate that a new timer exists and a call to [service_timers](#) is required

7.8.1 Detailed Description

Support for delayed and periodic events.

Date

2012

Author

Keith Brister

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

7.8.2 Macro Definition Documentation

7.8.2.1 #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](#).

7.8.2.2 #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 `lstimer.c`.

7.8.3 Typedef Documentation

7.8.3.1 typedef struct `lstimer_list_struct` `lstimer_list_t`

Everything we need to know about a timer.

7.8.4 Function Documentation

7.8.4.1 static void handler (int *sig*, `siginfo_t` * *si*, void * *dummy*) [static]

Service the signal.

Definition at line 190 of file `lstimer.c`.

```

{
    pthread_mutex_lock( &lstimer_mutex);
    service_timers();
    pthread_mutex_unlock( &lstimer_mutex);
}

```

7.8.4.2 void `lstimer_init` ()

Initialize the timer list and pthread stuff.

Definition at line 270 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);
}

```

7.8.4.3 void `lstimer_run` ()

Start up our thread.

Definition at line 284 of file `lstimer.c`.

```

{
    pthread_create( &lstimer_thread, NULL, lstimer_worker
, NULL);
}

```

7.8.4.4 void `lstimer_set_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 63 of file Istimer.c.

```

{
    int i;
    struct timespec now;

    // Time we were called. Delay is based on call time, not queued time
    //
    clock_gettime( CLOCK_REALTIME, &now);

    // Make sure our event is registered (saves a tiny bit of time later)
    //
    lsevents_preregister_event( event);

    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_set_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);
}

```

7.8.4.5 void Istimer_unset_timer(char * event)

Unsets all timers for the given event.

Definition at line 46 of file Istimer.c.

```

{
    int i;

    for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
        if( strcmp( event, lstimer_list[i].event) == 0) {

```

```

        lstimer_list[i].shots = 0;
    }
}
}

```

7.8.4.6 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 200 of file lstimer.c.

```

    {
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( "lstimer_worker: sigaction
        failed");
    exit( -1);
}

// Create the timer
//
sev.sigev_notify = SIGEV_SIGNAL;
sev.sigev_signo = SIGRTMIN;
sev.sigev_value.sival_ptr = &lstimer_timerid;
timer_create( CLOCK_REALTIME, &sev, &lstimer_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);

while( 1) {
    pthread_mutex_lock( &lstimer_mutex);

    while( new_timer == 0)
        pthread_cond_wait( &lstimer_cond, &lstimer_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( &lstimer_mutex);
}

```

```

    // Let the signals rain down
    //
    sigprocmask( SIG_UNBLOCK, &mask, NULL);
}
}

```

7.8.4.7 static void service_timers () [static]

Send events that are past due, due, or just about to be due.

Definition at line 118 of file ltimer.c.

```

{
    int
        i,
        found_active;

    ltimer_list_t *p;
    struct timespec now, then, soonest;
    struct itimerspec its;

    //
    // Did I remind you not to let this thread own the ltimer mutex outside of
    // this
    // service routine when SIGRTMIN is active?
    //
    // Call with ltimer_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<ltimer_active_timers; i++) {
        p = &(ltimer_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
                    ltimer_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);
}
}

```

7.8.5 Variable Documentation

7.8.5.1 `int lstimer_active_timers = 0` `[static]`

count of the number timers we are tracking

Definition at line 18 of file `lstimer.c`.

7.8.5.2 `pthread_cond_t lstimer_cond` `[static]`

allows us to be idle when there is nothing to do

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

7.8.5.3 `lstimer_list_t lstimer_list[LSTIMER_LIST_LENGTH]` `[static]`

Our timer list.

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

7.8.5.4 `pthread_mutex_t lstimer_mutex` `[static]`

protect the timer list

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

7.8.5.5 `pthread_t lstimer_thread` `[static]`

the timer thread

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

7.8.5.6 `timer_t lstimer_timerid` `[static]`

our real time timer

Definition at line 41 of file `lstimer.c`.

7.8.5.7 `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 `lstimer.c`.

7.9 md2cmds.c File Reference

Implements commands to run the md2 diffractometer attached to a PMAC controled by postgresql.


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

Data Structures

- struct [md2cmds_cmd_kv_struct](#)

Typedefs

- typedef struct
[md2cmds_cmd_kv_struct](#) [md2cmds_cmd_kv_t](#)

Functions

- int [md2cmds_abort](#) (const char *dummy)
abort the current motion and put the system into a known state /param dummy Unused here
- int [md2cmds_center](#) (const char *dummy)
Move centering and alignment tables as requested TODO: Implement.
- int [md2cmds_collect](#) (const char *dummy)
Collect some data.
- int [md2cmds_moveAbs](#) (const char *ccmd)
Move a motor to the position requested Returns non zero on error.
- int [md2cmds_moveRel](#) (const char *ccmd)
Move a motor to the position requested Returns non zero on error.
- int [md2cmds_phase_change](#) (const char *ccmd)
Move md2 devices to a preconfigured state.
- int [md2cmds_run_cmd](#) (const char *)
- int [md2cmds_rotate](#) (const char *dummy)
Spin 360 and make a video (recenter first, maybe)
- int [md2cmds_set](#) (const char *)
- int [md2cmds_settransferpoint](#) (const char *)
- int [md2cmds_test](#) (const char *dummy)
Run the test routine(s)
- int [md2cmds_transfer](#) (const char *dummy)
Transfer a sample.
- void [md2cmds_home_prep](#) ()
- int [md2cmds_home_wait](#) (double timeout_secs)
- void [md2cmds_move_prep](#) ()
prepare for new movements
- int [md2cmds_move_wait](#) (double timeout_secs)
Wait for all the motions requested to complete.
- int [md2cmds_is_moving](#) ()
returns non-zero if we think a motor is moving, 0 otherwise
- double [md2cmds_prep_axis](#) (lsppmac_motor_t *mp, double pos)
- void [md2cmds_organs_move_presets](#) (char *pay, char *paz, char *pcy, char *pcz, char *psz)
- int [md2cmds_phase_manualMount](#) ()
Go to the manual mount phase.
- int [md2cmds_phase_robotMount](#) ()
Go to robot mount phase.
- int [md2cmds_phase_center](#) ()
Go to center phase.

- int [md2cmds_phase_dataCollection](#) ()
Go to data collection phase.
- int [md2cmds_phase_beamLocation](#) ()
Go to beam location phase.
- int [md2cmds_phase_safe](#) ()
Go to safe phase.
- void [md2cmds_mvcenter_move](#) (double cx, double cy, double ax, double ay, double az)
Move the centering and alignment tables.
- void [md2cmds_maybe_done_moving_cb](#) (char *event)
Track how many motors are moving.
- void [md2cmds_maybe_done_homing_cb](#) (char *event)
Track motors homing.
- void [md2cmds_kappaphi_move](#) (double kappa_deg, double phi_deg)
- 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 xscale and yscale have units of microns per pixel.
- void [md2cmds_time_capz_cb](#) (char *event)
Time the capillary motion for the transfer routine.
- int [md2cmds_action_queue](#) (double timeout, char *action)
- void [md2cmds_action_wait](#) ()
pause until md2cmds_worker has finished running the command
- void * [md2cmds_worker](#) (void *dummy)
Our worker thread.
- void [md2cmds_coordsys_1_stopped_cb](#) (char *event)
- void [md2cmds_coordsys_2_stopped_cb](#) (char *event)
- void [md2cmds_coordsys_3_stopped_cb](#) (char *event)
- void [md2cmds_coordsys_4_stopped_cb](#) (char *event)
- void [md2cmds_coordsys_5_stopped_cb](#) (char *event)
- void [md2cmds_coordsys_7_stopped_cb](#) (char *event)
- 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
- int [md2cmds_moving_queue_wait](#) = 0
- pthread_cond_t [md2cmds_moving_cond](#)
wait for command to have been dequeued and run
- pthread_mutex_t [md2cmds_moving_mutex](#)
message passing between md2cmds and pg
- int [md2cmds_homing_count](#) = 0
We've asked a motor to home.
- pthread_cond_t [md2cmds_homing_cond](#)

- coordinate homing and homed*
- pthread_mutex_t [md2cmds_homing_mutex](#)
- our mutex;*
- int [md2cmds_moving_count](#) = 0
- char [md2cmds_cmd](#) [MD2CMDS_CMD_LENGTH]
- our command;*
- [lsredis_obj_t](#) * [md2cmds_md_status_code](#)
- static pthread_t [md2cmds_thread](#)
- static int [rotating](#) = 0
- flag: when omega is in position after a rotate we want to re-home omega*
- static double [md2cmds_capz_moving_time](#) = NAN
- static struct hsearch_data [md2cmds_hmap](#)
- static regex_t [md2cmds_cmd_regex](#)
- static [md2cmds_cmd_kv_t](#) [md2cmds_cmd_kvs](#) []

7.9.1 Detailed Description

Implements commands to run the md2 diffractometer attached to a PMAC controled by postgresql.

Date

2012

Author

Keith Brister

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Definition in file [md2cmds.c](#).

7.9.2 Typedef Documentation

7.9.2.1 typedef struct md2cmds_cmd_kv_struct md2cmds_cmd_kv_t

7.9.3 Function Documentation

7.9.3.1 int md2cmds_abort (const char * *dummy*)

abort the current motion and put the system into a known state /param dummy Unused here

Definition at line 1572 of file md2cmds.c.

```

{
//
// First priority is to close the shutter
//
if( fshut->moveAbs( fshut, 0))
    lslogging_log_message( "md2cmds_abort: for some reason
        the shutter close requested failed. Proceeding anyway.");

//
// Now stop all the motors
//
lspmac_abort();
if( md2cmds_move_wait( 10.0))
    lslogging_log_message( "md2cmds_abort: Some motors did
        not appear to stop. Proceeding with reset anyway");

```

```

//
// Now try to close the shutter (again)
//
if( fshut->moveAbs( fshut, 0))
    lslogging_log_message( "md2cmds_abort: for some reason
        the shutter close requested failed (2). Proceeding anyway.");

//
// Force the motion flags down
//
lspmac_SockSendDPLine( NULL, "m5075=0");

return 0;
}

```

7.9.3.2 int md2cmds_action_queue(double timeout, char * action)

Definition at line 1534 of file md2cmds.c.

```

{
    int rtn;
    struct timespec waitforit;

    if( timeout < 0.0) {
        rtn = pthread_mutex_lock( &md2cmds_mutex);
    } else {
        clock_gettime( CLOCK_REALTIME, &waitforit);

        waitforit.tv_sec += floor(timeout);

        waitforit.tv_nsec += (timeout - waitforit.tv_sec)*1.e9;
        while( waitforit.tv_nsec >= 1000000000) {
            waitforit.tv_sec++;
            waitforit.tv_nsec -= 1000000000;
        }

        rtn = pthread_mutex_timedlock( &md2cmds_mutex, &waitforit);
    }

    if( rtn == 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 {
        if( rtn == ETIMEDOUT)
            lslogging_log_message( "md2cmds_action_queue: %s not
                queued, operation timed out", action);
        else
            lslogging_log_message( "md2cmds_action_queue: %s not
                queued with error code %d", action, rtn);
    }
    return rtn;
}

```

7.9.3.3 void md2cmds_action_wait ()

pause until md2cmds_worker has finished running the command

Definition at line 1602 of file md2cmds.c.

```

{
    pthread_mutex_lock( &md2cmds_mutex);
    pthread_mutex_unlock( &md2cmds_mutex);
}

```

7.9.3.4 int md2cmds_center(const char * dummy)

Move centering and alignment tables as requested TODO: Implement.

Definition at line 1497 of file md2cmds.c.

```

    {
        return 0;
    }

```

7.9.3.5 int md2cmds_collect (const char * *dummy*)

Collect some data.

Parameters

<i>dummy</i>	Unused returns non-zero on error
--------------	----------------------------------

< index of shot to be taken
 < Exposure time (saved to compute shutter timeout)
 < start cnts
 < delta cnts
 < omega velocity cnts/msec
 < acceleration time (msec)
 < exposure time (msec)
 < unit to counts conversion
 < nominal zero offset
 < maximum acceleration allowed for omega
 < current kappa position in case we need to move phi only
 < current phi position in case we need to move kappa only
 < setup timeouts for shutter

Definition at line 1017 of file md2cmds.c.

```

    {
        long long skey;
        double exp_time;
        double p170;
        double p171;
        double p173;
        double p175;
        double p180;
        double u2c;
        double neutral_pos;
        double max_accel;
        double kappa_pos;
        double phi_pos;
        struct timespec now, timeout;
        int err;
        double move_time;
        int mmask;

        u2c = lsredis_getd( omega->u2c);
        neutral_pos = lsredis_getd( omega->neutral_pos);
        max_accel = lsredis_getd( omega->max_accel);

        mmask = 0;
        err = lspmac_est_move_time( &move_time, &mmask,
            the In position      apery,      1, "In",      0.0, // Aperture to
                                aperz,      1, "In",      0.0,
                                capy,      1, "In",      0.0, // Capillary /
            Beamstop to the In position
                                capz,      1, "In",      0.0,
                                scint,     1, "Cover",    0.0, // Hide the
            scintillator
                                blight_ud, 1, NULL,      0.0, // put
            the backlight down
                                NULL);

        err = lspmac_est_move_time_wait( move_time + 2.0,

```

```

        mmask, NULL);
if( err) {
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

//
// reset shutter has opened flag
//
lspmac_SockSendDPLine( NULL, "P3001=0 P3002=0");

while( 1) {
    lspg_nextshot_call();
    lspg_nextshot_wait();

    exp_time = lspg_nextshot.dsexp;

    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);

    if( lspg_nextshot.active) {
        if(
            //
            // Don't move if we are within 0.1 microns of our destination
            //
            (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)) {

                lslogging_log_message( "md2cmds_collect: moving
                center to cx=%f, cy=%f, ax=%f, ay=%f, az=%f",lspg_nextshot.cx,
                lspg_nextshot.cy, lspg_nextshot.ax, lspg_nextshot
                .ay, lspg_nextshot.az);

                err = lspmac_est_move_time( &move_time, &mmask,
                    cenx, 0, NULL, lspg_nextshot
                    .cx,
                    ceny, 0, NULL, lspg_nextshot
                    .cy,
                    alignx, 0, NULL, lspg_nextshot
                    .ax,
                    aligny, 0, NULL, lspg_nextshot
                    .ay,
                    alignz, 0, NULL, lspg_nextshot
                    .az,
                    NULL);

                if( err) {
                    lsevents_send_event( "Data Collection Aborted");
                    return 1;
                }

                err = lspmac_est_move_time_wait( move_time,
                    mmask, NULL);
                if( err) {
                    lsevents_send_event( "Data Collection Aborted");
                    return 1;
                }
            }
        }

        // Maybe move kappa and/or phi
        //
        if( !lspg_nextshot.dsphi_isnull || !lspg_nextshot
            .dskappa_isnull) {

            kappa_pos = lspg_nextshot.dskappa_isnull ?
                lspmac_getPosition( kappa) : lspg_nextshot.
                dskappa;
            phi_pos = lspg_nextshot.dsphi_isnull ?
                lspmac_getPosition( phi) : lspg_nextshot.
                dsphi;

```

```

lslogging_log_message( "md2cmds_collect: move
phy/kappa: kappa=%f phi=%f", kappa_pos, phi_pos);

err = lspmac_est_move_time( &move_time, &mmask,
                           kappa, 0, NULL, kappa_pos,
                           phi, 0, NULL, phi_pos,
                           NULL);

if( err) {
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

err = lspmac_est_move_time_wait( move_time + 2,
mmask, NULL);
if( err) {
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}
}

//
// Calculate the parameters we'll need to run the scan
//
p180 = lspg_nextshot.dsexp * 1000.0;
p170 = u2c * (lspg_nextshot.sstart + neutral_pos);
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 opened flag is down
// wait for the p3001=0 command to be noticed
//
clock_gettime( CLOCK_REALTIME, &now);
timeout.tv_sec = now.tv_sec + 10;
timeout.tv_nsec = now.tv_nsec;

err = 0;
pthread_mutex_lock( &lspmac_shutter_mutex);
while( err == 0 && lspmac_shutter_has_opened == 1)
    err = pthread_cond_timedwait( &lspmac_shutter_cond, &
    lspmac_shutter_mutex, &timeout);
pthread_mutex_unlock( &lspmac_shutter_mutex);

if( err == ETIMEDOUT) {
    pthread_mutex_unlock( &lspmac_shutter_mutex);
    lslogging_log_message( "md2cmds_collect: Timed out
    waiting for shutter to open. Data collection aborted.");
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

//
// Start the exposure
//
lspmac_set_motion_flags( &mmask, omega);
lspmac_SockSendDPline( "Exposure",
                      "&1 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);

//

```

```

// We could look for the "Exposure command accepted" event at this point.
//
//
// wait for the shutter to open
//
clock_gettime( CLOCK_REALTIME, &now);
timeout.tv_sec = now.tv_sec + 10;
timeout.tv_nsec = now.tv_nsec;

err = 0;
pthread_mutex_lock( &lspmac_shutter_mutex);
while( err == 0 && lspmac_shutter_has_opened == 0)
    err = pthread_cond_timedwait( &lspmac_shutter_cond, &
        lspmac_shutter_mutex, &timeout);

if( err == ETIMEDOUT) {
    pthread_mutex_unlock( &lspmac_shutter_mutex);
    lslogging_log_message( "md2cmds_collect: Timed out
        waiting for shutter to open. Data collection aborted.");
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

//
// wait for the shutter to close
//
clock_gettime( CLOCK_REALTIME, &now);
timeout.tv_sec = now.tv_sec + 4 + exp_time; // hopefully 4 seconds
// is long enough to never catch a legitimate shutter close and short enough to
// bail when something is really wrong
timeout.tv_nsec = now.tv_nsec;

err = 0;
while( err == 0 && lspmac_shutter_state == 1)
    err = pthread_cond_timedwait( &lspmac_shutter_cond, &
        lspmac_shutter_mutex, &timeout);
pthread_mutex_unlock( &lspmac_shutter_mutex);

if( err == ETIMEDOUT) {
    pthread_mutex_unlock( &lspmac_shutter_mutex);
    lslogging_log_message( "md2cmds_collect: Timed out
        waiting for shutter to close. Data collection aborted.");
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

//
// Signal the detector to start reading out
//
lspg_query_push( NULL, "SELECT px.unlock_diffractionmeter()");

//
// Update the shot status
//
lspg_query_push( NULL, "SELECT px.shots_set_state(%lld,
    'Writing')", skey);

//
// reset shutter has opened flag
//
lspmac_SockSendDPline( NULL, "P3001=0");

//
// Wait for omega to stop moving
//
if( md2cmds_move_wait( 10.0)) {
    lslogging_log_message( "md2cmds_collect: Giving up
        waiting for omega to stop moving. Data collection aborted.");
    lsevents_send_event( "Data Collection Aborted");
    return 1;
}

//
// Move the center/alignment stages to the next position
//
// TODO: position omega for the next shot. During data collection the
// motion program
// makes a good guess but for ortho snaps it is wrong. We should add an
// argument to the motion program
//

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)) {

        md2cmds_move_prep();
        md2cmds_mvcenter_move( lspg_nextshot.
        cx, lspg_nextshot.cy, lspg_nextshot.ax,
        lspg_nextshot.ay, lspg_nextshot.az);
    }
}
lsevents_send_event( "Data Collection Done");
return 0;
}

```

7.9.3.6 void md2cmds_coordsys_1_stopped_cb (char * event)

Definition at line 1837 of file md2cmds.c.

```

{

```

7.9.3.7 void md2cmds_coordsys_2_stopped_cb (char * event)

Definition at line 1839 of file md2cmds.c.

```

{

```

7.9.3.8 void md2cmds_coordsys_3_stopped_cb (char * event)

Definition at line 1841 of file md2cmds.c.

```

{

```

7.9.3.9 void md2cmds_coordsys_4_stopped_cb (char * event)

Definition at line 1843 of file md2cmds.c.

```

{

```

7.9.3.10 void md2cmds_coordsys_5_stopped_cb (char * event)

Definition at line 1845 of file md2cmds.c.

```

{

```

7.9.3.11 void md2cmds_coordsys_7_stopped_cb (char * event)

Definition at line 1847 of file md2cmds.c.

```

    {
}

```

7.9.3.12 void md2cmds_home_prep ()

Definition at line 72 of file md2cmds.c.

```

    {
pthread_mutex_lock( &md2cmds_homing_mutex);
md2cmds_homing_count = -1;
pthread_mutex_unlock( &md2cmds_homing_mutex);
}

```

7.9.3.13 int md2cmds_home_wait (double timeout_secs)

Definition at line 79 of file md2cmds.c.

```

    {
struct timespec timeout, now;
double isecs, fsecs;
int err;

clock_gettime( CLOCK_REALTIME, &now);

fsecs = modf( timeout_secs, &isecs);

timeout.tv_sec = now.tv_sec + (long)floor( isecs);
timeout.tv_nsec = now.tv_nsec + (long)floor( fsecs * 1.0e9);

timeout.tv_sec += timeout.tv_nsec / 1000000000;
timeout.tv_nsec %= 1000000000;

err = 0;
pthread_mutex_lock( &md2cmds_homing_mutex);
while( err == 0 && md2cmds_homing_count == -1)
    err = pthread_cond_timedwait( &md2cmds_homing_cond, &
        md2cmds_homing_mutex, &timeout);

if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "md2cmds_home_wait:
            unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
            timeout.tv_nsec);
    }
    pthread_mutex_unlock( &md2cmds_homing_mutex);
    return 1;
}

err = 0;
while( err == 0 && md2cmds_homing_count > 0)
    err = pthread_cond_timedwait( &md2cmds_homing_cond, &
        md2cmds_homing_mutex, &timeout);
pthread_mutex_unlock( &md2cmds_homing_mutex);

if( err != 0) {
    if( err != ETIMEDOUT)
        lslogging_log_message( "md2cmds_home_wait:
            unexpected error from timedwait: %d", err);

    return 1;
}
return 0;
}

```

7.9.3.14 void md2cmds_init ()

Initialize the md2cmds module.

Definition at line 1853 of file md2cmds.c.

```

    {
ENTRY hloader, *hrtnval;
int i, err;

pthread_mutexattr_t mutex_initializer;

pthread_mutexattr_init( &mutex_initializer);
pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

pthread_mutex_init( &md2cmds_mutex, &mutex_initializer);
pthread_cond_init( &md2cmds_cond, NULL);


pthread_mutex_init( &md2cmds_moving_mutex, &
    mutex_initializer);
pthread_cond_init( &md2cmds_moving_cond, NULL);

pthread_mutex_init( &md2cmds_homing_mutex, &
    mutex_initializer);
pthread_cond_init( &md2cmds_homing_cond, NULL);

err = regcomp( &md2cmds_cmd_regex, " *([^\ ]+) ([^\ ]+)\|\\
    .presets\\.)*([^\ ]*) *([^\ ]*)", REG_EXTENDED);
if( err != 0) {
    int nerrmsg;
    char *errmsg;

    nerrmsg = regerror( err, &md2cmds_cmd_regex, NULL, 0);
    if( nerrmsg > 0) {
        errmsg = calloc( nerrmsg, sizeof( char));
        nerrmsg = regerror( err, &md2cmds_cmd_regex, errmsg,
            nerrmsg);
        lslogging_log_message( "md2cmds_init: %s", errmsg);
        free( errmsg);
    }
}

md2cmds_md_status_code = lsredis_get_obj
    ( "md2_status_code");
lsredis_setstr( md2cmds_md_status_code, "
    7");

hcreate_r( 2 * sizeof(md2cmds_cmd_kvs)/sizeof(md2cmds_cmd_kvs
    [0]), &md2cmds_hmap);
for( i=0; i<sizeof(md2cmds_cmd_kvs)/sizeof(md2cmds_cmd_kvs
    [0]); i++) {
    hloader.key = md2cmds_cmd_kvs[i].k;
    hloader.data = md2cmds_cmd_kvs[i].v;
    err = hsearch_r( hloader, ENTER, &hrtnval, &md2cmds_hmap);
    if( err == 0) {
        lslogging_log_message( "md2cmds_init: hsearch_r
            returned an error for item %d: %s", i, strerror( errno));
    }
}
}
}

```

7.9.3.15 int md2cmds_is_moving ()

returns non-zero if we think a motor is moving, 0 otherwise

Definition at line 178 of file md2cmds.c.

```

    {
int rtn;

pthread_mutex_lock( &md2cmds_moving_mutex);
rtn = md2cmds_moving_count != 0;
pthread_mutex_unlock( &md2cmds_moving_mutex);

return rtn;
}

```

7.9.3.16 void md2cmds_kappaphi_move (double kappa_deg, double phi_deg)

Definition at line 995 of file md2cmds.c.

```

int kc, pc;

// coordinate system 7
// 1 << (coord sys no - 1) = 64

kc = md2cmds_prep_axis( kappa, kappa_deg);
pc = md2cmds_prep_axis( kappa, phi_deg);

// ;150          LS-CAT Move X, Y Absolute
// ;            Q20   = X Value
// ;            Q21   = Y Value
// ;            Q100  = 1 << (coord sys no - 1)

lspmac_SockSendDPLine( "kappaphi_move", "&7 Q20=%d
Q21=%d Q100=64", kc, pc);
}

```

7.9.3.17 void md2cmds_maybe_done_homing_cb(char * event)

Track motors homing.

Definition at line 971 of file md2cmds.c.

```

pthread_mutex_lock( &md2cmds_homing_mutex);

if( strstr( event, "Homing") == NULL) {
    if( md2cmds_homing_count != -1)
        md2cmds_homing_count = 1;
    else
        md2cmds_homing_count++;
} else {
    if( md2cmds_homing_count > 0)
        md2cmds_homing_count--;
}

if( md2cmds_homing_count != 0)
    lsredis_setstr( md2cmds_md_status_code,
        "%s", "4");

if( md2cmds_homing_count == 0)
    pthread_cond_signal( &md2cmds_homing_cond);

pthread_mutex_unlock( &md2cmds_homing_mutex);
}

```

7.9.3.18 void md2cmds_maybe_done_moving_cb(char * event)

Track how many motors are moving.

Definition at line 942 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 {
    //
    //
    if( md2cmds_moving_count > 0)
        md2cmds_moving_count--;
}

lsredis_setstr( md2cmds_md_status_code, "
%s", md2cmds_moving_count ? "4" : "3");

if( md2cmds_moving_count == 0)
    pthread_cond_signal( &md2cmds_moving_cond);
}

```

```
pthread_mutex_unlock( &md2cmds_moving_mutex);
}
```

7.9.3.19 void md2cmds_maybe_rotate_done_cb (char * event)

Now that we are done with the 360 rotation lets rehome right quick.

Definition at line 1458 of file md2cmds.c.

```

{
if( rotating) {
    rotating = 0;
    lsevents_send_event( "Rotate Done");
}
}
```

7.9.3.20 void md2cmds_move_prep ()

prepare for new movements

Definition at line 124 of file md2cmds.c.

```

{
pthread_mutex_lock( &md2cmds_moving_mutex);
md2cmds_moving_count = -1;
pthread_mutex_unlock( &md2cmds_moving_mutex);
}
```

7.9.3.21 int md2cmds_move_wait (double timeout_secs)

Wait for all the motions requested to complete.

Parameters

<i>timeout_secs</i>	Double value of seconds to wait
---------------------	---------------------------------

There are two waits involved: First to wait for the first "Moving" to be seen and second to wait for the last "In Position". The timeout specified here is the sum of the two.

returns 0 on success and 1 if we timedout.

Definition at line 141 of file md2cmds.c.

```

{
double isecs, fsecs;
struct timespec timeout, now;
int err;

clock_gettime( CLOCK_REALTIME, &now);

fsecs = modf( timeout_secs, &isecs);

timeout.tv_sec = now.tv_sec + (long)floor( isecs);
timeout.tv_nsec = now.tv_nsec + (long)floor( fsecs * 1.0e9);

timeout.tv_sec += timeout.tv_nsec / 1000000000;
timeout.tv_nsec %= 1000000000;

err = 0;
pthread_mutex_lock( &md2cmds_moving_mutex);
while( err == 0 && md2cmds_moving_count == -1)
    err = pthread_cond_timedwait( &md2cmds_moving_cond, &
        md2cmds_moving_mutex, &timeout);

if( err == ETIMEDOUT) {
    pthread_mutex_unlock( &md2cmds_moving_mutex);
}
```

```

    return 1;
}

err = 0;
while( err == 0 && md2cmds_moving_count > 0)
    err = pthread_cond_timedwait( &md2cmds_moving_cond, &
        md2cmds_moving_mutex, &timeout);
pthread_mutex_unlock( &md2cmds_moving_mutex);

if( err == ETIMEDOUT)
    return 1;
return 0;
}

```

7.9.3.22 int md2cmds_moveAbs (const char * ccmd)

Move a motor to the position requested Returns non zero on error.

Parameters

in	ccmd	The full command string to parse, ie, "moveAbs omega 180"
----	------	---

Definition at line 452 of file md2cmds.c.

```

{
char *cmd;
char *ignore;
char *ptr;
char *mtr;
char *pos;
double fpos;
char *endptr;
lspmac_motor_t *mp;
int err;

// ignore nothing
if( ccmd == NULL || *ccmd == 0) {
    return 1;
}

// 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 1;
}

// 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: missing motor
        name");
    free( cmd);
    return 1;
}

mp = lspmac_find_motor_by_name( mtr);
if( mp == NULL) {
    lslogging_log_message( "md2cmds_moveAbs: cannot find
        motor %s", mtr);
    free( cmd);
    return 1;
}

pos = strtok_r( NULL, " ", &ptr);
if( pos == NULL) {
    lslogging_log_message( "md2cmds_moveAbs: missing
        position");
    free( cmd);
    return 1;
}

```

```

}

fpos = strtod( pos, &endptr);
if( pos == endptr) {
    //
    // Maybe we have a preset. Give it a whirl
    // In any case we are done here.
    //
    err = lspmac_move_preset_queue( mp, pos);
    free( cmd);
    return err;
}

if( mp != NULL && mp->moveAbs != NULL) {
    wprintw( term_output, "Moving %s to %f\n", mtr, fpos);
    wnoutrefresh( term_output);
    err = mp->moveAbs( mp, fpos);
}

free( cmd);
return err;
}

```

7.9.3.23 int md2cmds_moveRel (const char * *ccmd*)

Move a motor to the position requested Returns non zero on error.

Parameters

in	<i>ccmd</i>	The full command string to parse, ie, "moveAbs omega 180"
----	-------------	---

Definition at line 531 of file md2cmds.c.

```

{
    char *cmd;
    char *ignore;
    char *ptr;
    char *mtr;
    char *pos;
    double fpos;
    char *endptr;
    lspmac_motor_t *mp;
    int err;

    // ignore nothing
    if( ccmd == NULL || *ccmd == 0) {
        return 1;
    }

    // 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 1;
    }

    // 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_moveRel: missing motor
            name");
        free( cmd);
        return 1;
    }

    mp = lspmac_find_motor_by_name( mtr);

    if( mp == NULL) {
        lslogging_log_message( "md2cmds_moveRel: cannot find
            motor %s", mtr);
    }
}

```

```

    free( cmd);
    return 1;
}

pos = strtok_r( NULL, " ", &ptr);
if( pos == NULL) {
    lslogging_log_message( "md2cmds_moveRel: missing
        position");
    free( cmd);
    return 1;
}

fpos = strtod( pos, &endptr);
if( pos == endptr) {
    //
    // No incrementnal position found
    //
    lslogging_log_message( "md2cmds_moveRel: no new
        position requested");
    return 1;
}

if( mp != NULL && mp->moveAbs != NULL) {
    wprintw( term_output, "Moving %s by %f\n", mtr, fpos);
    wnoutrefresh( term_output);
    err = mp->moveAbs( mp, lspmac_getPosition(mp) +
        fpos);
}

free( cmd);
return err;
}

```

7.9.3.24 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 915 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_axis( cenx, cx);
cy_cts = md2cmds_prep_axis( ceny, cy);
ax_cts = md2cmds_prep_axis( alignx, ax);
ay_cts = md2cmds_prep_axis( aligny, ay);
az_cts = md2cmds_prep_axis( alignz, az);

lspmac_SockSendDPLine( NULL, "%2 Q100=2 Q20=%.1f
    Q21=%.1f B150R", cx_cts, cy_cts);
lspmac_SockSendDPLine( "mvcenter_move", "%3 Q100=4
    Q30=%.1f Q31=%.1f Q32=%.1f B160R", ax_cts, ay_cts, az_cts);
}

```

7.9.3.25 void md2cmds_organs_move_presets (char * pay, char * paz, char * pcy, char * pcz, char * psz)

Definition at line 211 of file md2cmds.c.


```

    {
double ay, az, cy, cz, sz;
int cay, caz, ccy, ccz, csz;
int err;

err = lsredis_find_preset( apery->name, pay, &ay)
;
if( err == 0) {
    lslogging_log_message( "md2cmds_move_organs_presets:
        no preset '%s' for motor '%s'", pay, apery->name);
    return;
}

err = lsredis_find_preset( aperz->name, paz, &az)
;
if( err == 0) {
    lslogging_log_message( "md2cmds_move_organs_presets:
        no preset '%s' for motor '%s'", paz, aperz->name);
    return;
}

err = lsredis_find_preset( capy->name, pcy, &cy);
if( err == 0) {
    lslogging_log_message( "md2cmds_organ_move_presets:
        no preset '%s' for motor '%s'", pcy, capy->name);
    return;
}

err = lsredis_find_preset( capz->name, pcz, &cz);
if( err == 0) {
    lslogging_log_message( "md2cmds_organ_move_presets:
        no preset '%s' for motor '%s'", pcz, capz->name);
    return;
}

err = lsredis_find_preset( scint->name, psz, &sz)
;
if( err == 0) {
    lslogging_log_message( "md2cmds_organ_move_presets:
        no preset '%s' for motor '%s'", psz, scint->name);
    return;
}

cay = md2cmds_prep_axis( apery, ay);
caz = md2cmds_prep_axis( aperz, az);
ccy = md2cmds_prep_axis( capy, cy);
ccz = md2cmds_prep_axis( capz, cz);
csz = md2cmds_prep_axis( scint, sz);

//
// 170          LS-CAT Move U, V, W, X, Y, Z Absolute
//              Q40      = X Value
//              Q41      = Y Value
//              Q42      = Z Value
//              Q43      = U Value
//              Q44      = V Value
//              Q45      = W Value
//

lspmac_SockSendDPLine( "organs", "&5 Q40=0 Q41=%d Q42=%d
    Q43=%d Q44=%d Q45=%d Q100=16 B170R", cay, caz, ccy, ccz, csz);
}

```

7.9.3.26 int md2cmds_phase_beamLocation ()

Go to beam location phase.

Definition at line 774 of file md2cmds.c.

```

    {
double move_time;
int mmask, err;

lsevents_send_event( "Mode beamLocation Starting");

mmask = 0;
err = lspmac_est_move_time( &move_time, &mmask,
    //motor jog, preset, position if no preset

    NULL, 0.0, kappa, 0,

```

```

        omega,      0, NULL,      0.0,
        apery,      0, "In",      0.0,
        aperz,      0, "In",      0.0,
        capy,      0, "In",      0.0,
        capz,      0, "In",      0.0,
        scint,      0, "Scintillator", 0.0,
        blight,     1, NULL,      0.0,
        blight_ud,  1, NULL,      0.0,
        zoom,       0, NULL,      1.0,
        cryo,       1, NULL,      0.0,
        fluo,       1, NULL,      0.0,
        NULL);

if( err) {
    lsevents_send_event( "Mode beamLocation Aborted");
    return err;
}

err = lspmac_est_move_time_wait( move_time + 2.0,
    mmask, blight_ud, cryo, fluo, NULL);
if( err) {
    lsevents_send_event( "Mode beamLocation Aborted");
    return err;
}

lsevents_send_event( "Mode beamLocation Done");
return 0;
}

```

7.9.3.27 int md2cmds_phase_center()

Go to center phase.

Definition at line 699 of file md2cmds.c.

```

{
double move_time;
int mmask, err;

lsevents_send_event( "Mode center Starting");
//

// Move 'em

//

mmask = 0;
err = lspmac_est_move_time( &move_time, &mmask,
    omega,      0, NULL,      0.0,
    kappa,      0, NULL,      0.0,
    phi,        0, NULL,      0.0,
    apery,      0, "In",      0.0,
    aperz,      0, "In",      0.0,
    capy,      0, "In",      0.0,
    capz,      0, "In",      0.0,
    scint,      0, "Cover",    0.0,
    blight_ud,  1, NULL,      0.0,
    zoom,       0, NULL,      1.0,
    cryo,       1, NULL,      0.0,
    fluo,       1, NULL,      0.0,
    NULL);

if( err) {
    lsevents_send_event( "Mode center Aborted");
    return err;
}

err = lspmac_est_move_time_wait( move_time + 2.0,
    mmask, cryo, fluo, NULL);
if( err) {
    lsevents_send_event( "Mode center Aborted");
    return err;
}

lsevents_send_event( "Mode center Done");
return 0;
}

```

7.9.3.28 int 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 855 of file md2cmds.c.

```

{
    char *cmd;
    char *ignore;
    char *ptr;
    char *mode;
    int err;

    if( ccmd == NULL || *ccmd == 0 )
        return 1;

    // 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 1;
    }

    //

    // 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" );
        return 1;
    }

    if( md2cmds_is_moving() ) {
        int err;
        lspmac_SockSendDPControlChar( "Aborting Motions
            ", '\x01' );
        err = md2cmds_move_wait( 2.0 );
        if( err ) {
            lslogging_log_message( "md2cmds_phase_change: Timed
                out waiting for previous moves to finish" );
            return 1;
        }
    }

    //

    // Tangled web. Probably not worth fixing.

    //

    O(N) but N is 6.

    //

    if( strcmp( mode, "manualMount" ) == 0 ) {
        err = md2cmds_phase_manualMount();
    }
}

```

```

    } else if( strcmp( mode, "robotMount") == 0) {
        err = md2cmds_phase_robotMount();
    } else if( strcmp( mode, "center") == 0) {
        err = md2cmds_phase_center();
    } else if( strcmp( mode, "dataCollection") == 0) {
        err = md2cmds_phase_dataCollection();
    } else if( strcmp( mode, "beamLocation") == 0) {
        err = md2cmds_phase_beamLocation();
    } else if( strcmp( mode, "safe") == 0) {
        err = md2cmds_phase_safe();
    }

    free( cmd);
    return err;
}

```

7.9.3.29 int md2cmds_phase_dataCollection ()

Go to data collection phase.

Definition at line 738 of file md2cmds.c.

```

{
    double move_time;
    int mmask, err;

    lsevents_send_event( "Mode dataCollection Starting");

    mmask = 0;
    err = lspmac_est_move_time( &move_time, &mmask,
                                apery,      1, "In",      0.0,
                                aperz,      1, "In",      0.0,
                                capy,       1, "In",      0.0,
                                capz,       1, "In",      0.0,
                                scint,      1, "Cover",    0.0,
                                blight,     1, NULL,      0.0,
                                blight_ud,  1, NULL,      0.0,
                                cryo,       1, NULL,      0.0,
                                fluo,       1, NULL,      0.0,
                                NULL);

    if( err) {
        lsevents_send_event( "Mode dataCollection Aborted");
        return err;
    }

    err = lspmac_est_move_time_wait( move_time + 2.0,
                                    mmask, apery, aperz, capy, capz, scint, blight_ud,
                                    cryo, fluo, NULL);
    if( err) {
        lsevents_send_event( "Mode dataCollection Aborted");
        return err;
    }

    lsevents_send_event( "Mode dataCollection Done");
    return 0;
}

```

7.9.3.30 int md2cmds_phase_manualMount ()

Go to the manual mount phase.

Definition at line 612 of file md2cmds.c.

```

{
    double move_time;
    int mmask, err;

    lsevents_send_event( "Mode manualMount Starting");
    //
    // Move stuff
    //
    mmask = 0;
    err = lspmac_est_move_time( &move_time, &mmask,
                                kappa,      0, "manualMount", 0.0,
                                omega,     0, "manualMount", 0.0,
                                phi,       0, NULL,          0.0,

```

```

        aperz,      1, "Cover",      0.0,
        capz,       1, "Cover",      0.0,
        scint,      1, "Cover",      0.0,
        blight,     1, NULL,          0.0,
        blight_ud,  1, NULL,          0.0,
        cryo,       1, NULL,          1.0,
        fluo,       1, NULL,          0.0,
        zoom,      0, NULL,          1.0,
        NULL);

if( err) {
    lsevents_send_event( "Mode manualMount Aborted");
    return err;
}

//

// Wait for motion programs

//

err = lspmac_est_move_time_wait( move_time+2.0,
                                mmask, aperz, scint, blight_ud, cryo, fluo, NULL);
if( err) {
    lsevents_send_event( "Mode manualMount Aborted");
    return err;
}

lsevents_send_event( "Mode manualMount Done");
return 0;
}

```

7.9.3.31 int md2cmds_phase_robotMount ()

Go to robot mount phase.

Definition at line 656 of file md2cmds.c.

```

{
    double move_time;
    int mmask, err;

    lsevents_send_event( "Mode robotMount Starting");

    md2cmds_home_prep();

    //

    // Move 'em

    //

    lspmac_home1_queue( kappa);
    lspmac_home1_queue( omega);

    mmask = 0;
    err = lspmac_est_move_time( &move_time, &mmask,
                                phi,      0, NULL,      0.0,
                                apery,    1, "In",        0.0,
                                aperz,    1, "In",        0.0,
                                capz,     1, "Cover",      0.0,
                                scint,    1, "Cover",      0.0,
                                blight,   1, NULL,          0.0,
                                blight_ud, 1, NULL,          0.0,
                                cryo,     1, NULL,          1.0,
                                fluo,     1, NULL,          0.0,
                                zoom,     0, NULL,          1.0,
                                NULL);

    err = lspmac_est_move_time_wait( move_time + 2.0,
                                    mmask, apery, aperz, capz, scint, blight_ud, cryo,

```

```

        fluo, NULL);
if( err) {
    lsevents_send_event( "Mode robotMount Aborted");
    return err;
}

err = md2cmds_home_wait( 60.0);
if( err) {
    lsevents_send_event( "Mode robotMount Aborted");
    return err;
}

lsevents_send_event( "Mode robotMount Done");
return 0;
}

```

7.9.3.32 int md2cmds_phase_safe ()

Go to safe phase.

Definition at line 813 of file md2cmds.c.

```

{
double move_time;
int mmask, err;

lsevents_send_event( "Mode safe Starting");

mmask = 0;
err = lspmac_est_move_time( &move_time, &mmask,
                           //motor jog, preset, position if no preset

                           kappa,      0, NULL,      0.0,
                           omega,      0, NULL,      0.0,
                           apery,      1, "In",      0.0,
                           aperz,      1, "Cover",    0.0,
                           capy,       1, "In",      0.0,
                           capz,       1, "Cover",    0.0,
                           scint,      1, "Cover",    0.0,
                           blight,     1, NULL,      0.0,
                           blight_ud,  1, NULL,      0.0,
                           zoom,       0, NULL,      1.0,
                           cryo,       1, NULL,      0.0,
                           fluo,       1, NULL,      0.0,
                           NULL);

if( err) {
    lsevents_send_event( "Mode safe Aborted");
    return err;
}

err = lspmac_est_move_time_wait( move_time + 2.0,
                                mmask, apery, aperz, capy, capz, scint, blight_ud,
                                cryo, fluo, NULL);
if( err) {
    lsevents_send_event( "Mode safe Aborted");
    return err;
}

lsevents_send_event( "Mode safe Done");
return 0;
}

```

7.9.3.33 double md2cmds_prep_axis (lspmac_motor_t * mp, double pos)

Definition at line 189 of file md2cmds.c.

```

{
double rtn;
double u2c;
double neutral_pos;

pthread_mutex_lock( &(mp->mutex));

```

```

u2c          = lsredis_getd( mp->u2c);
neutral_pos = lsredis_getd( mp->neutral_pos);

mp->motion_seen = 0;
mp->not_done    = 1;

rtn = u2c * (pos + neutral_pos);

pthread_mutex_unlock( &(mp->mutex));

return rtn;
}

```

7.9.3.34 int md2cmds_rotate (const char * *dummy*)

Spin 360 and make a video (recenter first, maybe)

Parameters

<i>dummy</i>	Unused returns non-zero on error
--------------	----------------------------------

Definition at line 1293 of file md2cmds.c.

```

{
double cx, cy, ax, ay, az,  zm;
double  bax, bay, baz;
int mmask;
int err;
double move_time;

mmask = 0;
//
// BLUMax disables scintillator here.
//

//
// get the new center information
//
lspg_getcenter_call();
lspg_getcenter_wait();

// put up the back light
blight_ud->moveAbs( blight_ud, 1);

//
// Get ready to move our motors
md2cmds_home_prep();

//
// make sure omega is homed
//
lspmac_homed_queue( omega);
//
// Grab the current positions
//
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.no_rows_returned) {
    //
    // Always specify zoom even if no other center information is found
    //
    zm = 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) {
        zm = lspg_getcenter.zoom;
    }
}

```

```

    } else {
        zm = 1.0;
    }

    if( lspg_getcenter.dcx_isnull == 0)
        cx += lspg_getcenter.dcx;

    if( lspg_getcenter.dcy_isnull == 0)
        cy += lspg_getcenter.dcy;

    //
    // Slightly complicated procedure for alignment stage since we might want
    // to update
    // the presets. Use the preset Back_Vector to calculate the new Back
    // preset from our
    // current position.
    //
    if( lspg_getcenter.dax_isnull == 0) {
        err = lsredis_find_preset( "align.x", "Back_Vector", &
            bax);
        if( err == 0)
            bax = 0.0;
        bax += lspg_getcenter.dax;
        lsredis_set_preset( "align.x", "Back", bax);

        ax += lspg_getcenter.dax;
        lsredis_set_preset( "align.x", "Beam", ax);
    }

    if( lspg_getcenter.day_isnull == 0) {
        err = lsredis_find_preset( "align.y", "Back_Vector", &
            bay);
        if( err == 0)
            bay = 0.0;
        bay += lspg_getcenter.day;
        lsredis_set_preset( "align.y", "Back", bay);

        ay += lspg_getcenter.day;
        lsredis_set_preset( "align.y", "Beam", ay);
    }

    if( lspg_getcenter.daz_isnull == 0) {
        err = lsredis_find_preset( "align.z", "Back_Vector", &
            baz);
        if( err == 0)
            baz = 0.0;
        baz += lspg_getcenter.daz;
        lsredis_set_preset( "align.z", "Back", baz);

        az += lspg_getcenter.daz;
        lsredis_set_preset( "align.z", "Beam", az);
    }
}
lspg_getcenter_done();

if( lspmac_est_move_time( &move_time, &mmask,
    scint, 1, "Cover", 0.0,
    capz, 1, "Cover", 0.0,
    cenx, 0, NULL, cx,
    ceny, 0, NULL, cy,
    alignx, 0, NULL, ax,
    aligny, 0, NULL, ay,
    alignz, 0, NULL, az,
    zoom, 1, NULL, zm,
    NULL)) {
    lslogging_log_message( "md2cmds_rotate: organ motion
        request failed");
    lsevents_send_event( "Rotate Aborted");
    return 1;
}

if( lspmac_est_move_time_wait( move_time + 2.0,
    mmask, scint, capz, zoom, NULL)) {
    lslogging_log_message( "md2cmds_rotate: organ motion
        timed out %f seconds", move_time + 2.0);
    lsevents_send_event( "Rotate Aborted");
    return 1;
}

if( md2cmds_home_wait( 20.0)) {
    lslogging_log_message( "md2cmds_rotate: homing motors
        timed out. Rotate aborted");
    lsevents_send_event( "Rotate Aborted");
    return 1;
}

```



```

// 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));

lslogging_log_message( "md2cmds_rotate: done with
                applycenter");
lspmac_video_rotate( 4.0);
lslogging_log_message( "md2cmds_rotate: starting
                rotation");
rotating = 1;

return 0;
}

```

7.9.3.35 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 1443 of file md2cmds.c.

```

{
    struct tm t;
    int usecs;

    localtime_r( &(omega_zero_time.tv_sec), &t);

    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)));
}

```

7.9.3.36 void md2cmds_run ()

Start up the thread.

Definition at line 1903 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( ".+ (Moving|In Position)",
                md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "(.+) (Homing|Homed)",
                md2cmds_maybe_done_homing_cb);
    lsevents_add_listener( "capz (Moving|In Position)",
                md2cmds_time_capz_cb);
    lsevents_add_listener( "Coordsys 1 Stopped",
                md2cmds_coordsys_1_stopped_cb);
    lsevents_add_listener( "Coordsys 2 Stopped",
                md2cmds_coordsys_2_stopped_cb);
    lsevents_add_listener( "Coordsys 3 Stopped",
                md2cmds_coordsys_3_stopped_cb);
    lsevents_add_listener( "Coordsys 4 Stopped",
                md2cmds_coordsys_4_stopped_cb);
    lsevents_add_listener( "Coordsys 5 Stopped",
                md2cmds_coordsys_5_stopped_cb);
    lsevents_add_listener( "Coordsys 7 Stopped",
                md2cmds_coordsys_7_stopped_cb);
    lsevents_add_listener( "cam.zoom Moving",
                md2cmds_set_scale_cb);
}

```

7.9.3.37 int md2cmds_run_cmd (const char * cmd)

Definition at line 1616 of file md2cmds.c.

```

{
    int err, i;
    lspmac_motor_t *mp;
    regmatch_t pmatch[16];
    char cp[64];

    if( strlen(cmd) > sizeof( cp)-1) {
        lslogging_log_message( "md2cmds_run_cmd: command too
            long '%s'", cmd);
        return 1;
    }

    err = regexec( &md2cmds_cmd_regex, cmd, 16, pmatch, 0);
    if( err) {
        lslogging_log_message( "md2cmds_run_cmd: no match
            found from '%s'", cmd);
        return 1;
    }

    for( i=0; i<16; i++) {
        if( pmatch[i].rm_so == -1)
            continue;
        lslogging_log_message( "md2cmds_run_cmd: %d '%.*s'", i
            , pmatch[i].rm_eo - pmatch[i].rm_so, cmd+pmatch[i].rm_so);
    }

    //
    // get motor name
    //
    snprintf( cp, sizeof( cp)-1, "%.*s", pmatch[4].rm_eo - pmatch[4].rm_so, cmd+
        pmatch[4].rm_so);
    cp[sizeof( cp)-1] = 0;

    mp = lspmac_find_motor_by_name( cp);
    if( mp == NULL) {
        lslogging_log_message( "md2cmds_run_cmd: could not
            find motor '%s'", cp);
        return 1;
    }

    if( pmatch[5].rm_so != -1) {
        if( strncmp( cmd+pmatch[5].rm_so, "home", pmatch[5].rm_eo-pmatch[5].rm_so)
            ==0) {
            lslogging_log_message( "md2cmds_run_cmd: homing
                motor '%s'", cp);
            lspmac_home1_queue( mp);
        } else if( strncmp( cmd+pmatch[5].rm_so, "stop", pmatch[5].rm_eo-pmatch[5].
            rm_so)==0) {
            lslogging_log_message( "md2cmds_run_cmd: stoping
                motor '%s'", cp);
            lspmac_abort();
        }
    }

    return 0;
}

```

7.9.3.38 int md2cmds_set (const char * cmd)

Definition at line 1715 of file md2cmds.c.

```

{
    int err;
    lsredis_obj_t *p;
    lspmac_motor_t *mp;
    regmatch_t pmatch[16];
    char cp[64];
    char *rp;

    if( strlen(cmd) > sizeof( cp)-1) {
        lslogging_log_message( "md2cmds_set: command too long
            '%s'", cmd);
        return 1;
    }
}

```

```

lslogging_log_message( "md2cmds_set: recieved '%s'", cmd
);

err = regexec( &md2cmds_cmd_regex, cmd, 16, pmatch, 0);
if( err) {
    lslogging_log_message( "md2cmds_set: no match found
        from '%s'", cmd);
    return 1;
}

if( pmatch[2].rm_so == -1) {
    lslogging_log_message( "md2cmds_set: could not parse
        preset name from '%s'", cmd);
    return 1;
}

//
// get motor name
//
snprintf( cp, sizeof( cp)-1, "%.*s", pmatch[3].rm_eo - pmatch[3].rm_so, cmd+
    pmatch[3].rm_so);
cp[sizeof( cp)-1] = 0;

mp = lspmac_find_motor_by_name( cp);
if( mp == NULL) {
    lslogging_log_message( "md2cmds_set: could not find
        motor '%s'", cp);
    return 1;
}

//
// get redis preset position name
//

p = lsredis_get_obj( "%.*s.position", pmatch[2].rm_eo - pmatch
    [2].rm_so, cmd+pmatch[2].rm_so);
if( p == NULL) {
    lslogging_log_message( "md2cmds_set: could not find
        preset name in '%s'", cmd);
    return 1;
}

rp = lsredis_getstr( mp->redis_position);

//
// set the preset to the current position
//
lsredis_setstr( p, "%s", rp);
lsevents_send_event( "Preset Changed %s", p->events_name
);

free( rp);
return 0;
}

```

7.9.339 void md2cmds_set_scale_cb (char * event)

Fix up xscale and yscale when zoom changes xscale and yscale have units of microns per pixel.

Definition at line 1470 of file md2cmds.c.

```

{
    int mag;
    lsredis_obj_t *p1, *p2;
    char *vp;

    pthread_mutex_lock( &zoom->mutex);
    mag = zoom->requested_position;
    pthread_mutex_unlock( &zoom->mutex);

    p1 = lsredis_get_obj( "cam.xScale");
    p2 = lsredis_get_obj( "cam.zoom.%d.ScaleX", mag);

    vp = lsredis_getstr( p2);
    lsredis_setstr( p1, vp);
    free( vp);

    p1 = lsredis_get_obj( "cam.yScale");
    p2 = lsredis_get_obj( "cam.zoom.%d.ScaleY", mag);
}

```

```

    vp = lsredis_getstr( p2);
    lsredis_setstr( p1, vp);
    free( vp);
}

```

7.9.3.40 int md2cmds_settransferpoint (const char * *cmd*)

Definition at line 1665 of file md2cmds.c.

```

{
    double ax, ay, az, cx, cy;

    md2cmds_home_prep();

    //
    // Home Kappa
    //
    lspmac_home1_queue( kappa);

    //
    // Home omega
    //
    lspmac_home1_queue( omega);

    //
    // wait for kappa cause we can't home phi until kappa's done
    //
    lspmac_moveabs_wait( kappa, 60.0);

    //
    // Home phi (whatever that means)
    //
    lspmac_home1_queue( phi);

    //
    // Wait for the homing routines to finish
    //
    if( md2cmds_home_wait( 30.0)) {
        lslogging_log_message( "md2cmds_transfer: homing
            routines taking too long. Aborting transfer.");
        lsevents_send_event( "Settransferpoint Aborted");
        return 1;
    }

    //
    // get positions we'll be needed to report to postgres
    //
    ax = lspmac_getPosition(algnx);
    ay = lspmac_getPosition(algny);
    az = lspmac_getPosition(algnz);
    cx = lspmac_getPosition(cenx);
    cy = lspmac_getPosition(ceny);

    lspg_query_push( NULL, "SELECT px.settransferpoint( %0.3f,
        %0.3f, %0.3f, %0.3f)", ax, ay, az, cx, cy);

    lsevents_send_event( "Settransferpoint Done");
    return 0;
}

```

7.9.3.41 int md2cmds_test (const char * *dummy*)

Run the test routine(s)

Parameters

<i>dummy</i>	Unused
--------------	--------

Definition at line 1610 of file md2cmds.c.

```

{
    lstest_main();
    return 0;
}

```

7.9.3.42 void md2cmds_time_capz_cb (char * event)

Time the capillary motion for the transfer routine.

< track the time spent moving capz

Definition at line 1504 of file md2cmds.c.

```

{
static struct timespec capz_timestarted;
struct timespec now;
int nsec, sec;

if( strstr( event, "Moving") != NULL) {
    clock_gettime( CLOCK_REALTIME, &capz_timestarted);
} else {
    clock_gettime( CLOCK_REALTIME, &now);

    sec = now.tv_sec - capz_timestarted.tv_sec;
    nsec = 0;
    if( now.tv_nsec > capz_timestarted.tv_nsec) {
        sec--;
        nsec += 1000000000;
    }
    nsec += now.tv_nsec - capz_timestarted.tv_nsec;
    md2cmds_capz_moving_time = sec + nsec / 1000000000.
    ;
}
}

```

7.9.3.43 int md2cmds_transfer (const char * dummy)

Transfer a sample.

Parameters

<i>dummy</i>	Unused
--------------	--------

Definition at line 269 of file md2cmds.c.

```

{
int nextsample, abort_now;
double esttime;
double ax, ay, az, cx, cy, horz, vert, oref;
int err;
int mmask;
double move_time;

nextsample = lspg_nextsample_all( &err);
if( err) {
    lslogging_log_message( "md2cmds_transfer: no sample
        requested to be transfered, false alarm");
    return 1;
}

//
// BLUMax sets up an abort dialogbox here.  Probably we should figure out how
// we are going to handle that.
//

//
// Wait for motors to stop
//
if( md2cmds_is_moving()) {
    lslogging_log_message( "md2cmds_transfer: Waiting for
        previous motion to finish");
    if( md2cmds_move_wait( 30.0)) {
        lslogging_log_message( "md2cmds_transfer: Timed out
            waiting for previous motion to finish.  Aborting transfer");
    }
}

//
// get positions we'll be needed to report to postgres
//
ax = lspmac_getPosition(alignedx);
ay = lspmac_getPosition(alignedy);

```

```

az = lspmac_getPosition(algnz);
cx = lspmac_getPosition(cenx);
cy = lspmac_getPosition(ceny);
oref = lsredis_getd(lsredis_get_obj( "
    omega.reference")) * M_PI/180.;

horz = cx * cos(oref) + cy * sin(oref);
vert = cx * sin(oref) - cy * cos(oref);

if( lsredis_getd( capz->u2c) <= 0.0 || lsredis_getd
    ( capz->max_speed) <= 0.0 || lsredis_getd( capz->
    max_accel) <= 0.0) {
    esttime = 0.0;
} else {

    // Here we assume moving the capillary is the rate limiting step in
    // preparing the MD2.
    //
    // TODO: look at factors in which something besides the capillary determines
    // the time such as if the scintillator is out.
    //
    // pretend we are going to zero instead of the "Out" position. We should
    // probably arrange for
    // neutralPosition such that "Out" is zero.
    //
    // This also treats S curve acceleration as taking the same time as linear
    // acceleration.
    //
    esttime = lspmac_getPosition( capz)/lsredis_getd
        ( capz->u2c)/(lsredis_getd( capz->max_speed));
    // Time if we moved at constant velocity
    esttime += lsredis_getd( capz->max_speed)/
        lsredis_getd(capz->max_accel);
    // Correction for time spent accelerating
    esttime /= 1000.;
    // convert from milliseconds to seconds
}

lspg_starttransfer_call( nextsample,
    lspmac_getBIPosition( sample_detected), ax,
    ay, az, horz, vert, esttime);

mmask = 0;
err = lspmac_est_move_time( &move_time, &mmask,
    apery,      1, "In",      0.0,
    aperz,      1, "Cover",   0.0,
    capy,       1, "In",      0.0,
    capz,       1, "Cover",   0.0,
    scint,      1, "Cover",   0.0,
    blight_ud,  1, NULL,      0.0,
    fluo,       1, NULL,      0.0,
    NULL);

md2cmds_home_prep();

//
// Home Kappa
//
lspmac_home1_queue( kappa);

//
// Home omega
//
lspmac_home1_queue( omega);

//
// wait for kappa cause we can't home phi until kappa's done
//
lspmac_moveabs_wait( kappa, 60.0);

//
// Home phi (whatever that means)
//
lspmac_home1_queue( phi);

// Now let's get back to postgresql (remember our query so long ago?)
//
lspg_starttransfer_wait();

//
// It's possible that the sample that's mounted is unknown to the robot.
// If so then we need to abort after we're done moving stuff
//
if( lspg_starttransfer.no_rows_returned ||
    lspg_starttransfer.starttransfer != 1)
    abort_now = 1;

```

```

else
    abort_now = 0;

lspg_starttransfer_done();

//
// Wait for the homing routines to finish
//
if( md2cmds_home_wait( 30.0) ) {
    lslogging_log_message( "md2cmds_transfer: homing
        routines taking too long. Aborting transfer.");
    lsevents_send_event( "Transfer Aborted");
    return 1;
}

//
// Wait for all those other motors to stop moving
//
err = lspmac_est_move_time_wait( move_time + 2.0,
    mmask, apery, aperz, capy, capz, scint, blight_ud,
    fluo, NULL);
if( err ) {
    lsevents_send_event( "Transfer Aborted");
    return 1;
}

// TODO: check that all the motors are where we told them to go
//

//
// see if we have a sample mounted problem (is abort_now misnamed?)
//
if( abort_now ) {
    lslogging_log_message( "md2cmds_transfer: Apparently
        there is a sample mounted already but we don't know where it is supposed to go");
    lsevents_send_event( "Transfer Aborted");
    return 1;
}

// refuse to go on if we do not have positive confirmation that the backlight
// is down and the
// fluorescence detector is back (TODO: how about all those organs?)
//
if( lspmac_getBIPosition( blight_down) != 1 ||
    lspmac_getBIPosition( fluor_back) != 1) {
    lslogging_log_message( "md2cmds_transfer: It looks
        like either the back light is not down or the fluorescence dectector is not back");
    lsevents_send_event( "Transfer Aborted");
    return 1;
}

//
// Wait for the robot to unlock the cryo which signals us that we need to
// move the cryo back and drop air rights
//
lspg_waitcryo_all();

// Move the cryo back
//
cryo->moveAbs( cryo, 1);
lspmac_moveabs_wait( cryo, 10.0);

// simplest query yet!
lspg_query_push( lspg_waitcryo_cb, "SELECT
    px.dropairrights()");

// wait for the result
// TODO: find an easy way out of this in case of error
//
lspg_getcurrentsampleid_wait_for_id(
    nextsample);

// grab the airrights again
//
lspg_demandairrights_all();

lsevents_send_event( "Transfer Done");

return 0;
}

```

7.9.3.44 void* md2cmds_worker (void * dummy)

Our worker thread.

Parameters

<i>dummy</i>	[in] Unused but required by protocol
--------------	--------------------------------------

Definition at line 1780 of file md2cmds.c.

```

{

ENTRY hsearcher, *hrtnval;
char theCmd[32], *sp;
int i, err;
md2cmds_cmd_kv_t *cmdp;

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
        );

    //
    // pull out the command name itself from the string we were given
    //
    for( i=0, sp=md2cmds_cmd; i<sizeof( theCmd)-1; i++, sp++) {
        if( *sp == 0 || *sp == ' ' ) {
            theCmd[i] = 0;
            break;
        }
        theCmd[i] = *sp;
    }
    theCmd[sizeof(theCmd)-1]=0;

    hsearcher.key = theCmd;
    hsearcher.data = NULL;

    errno = 0;
    err = hsearch_r( hsearcher, FIND, &hrtnval, &md2cmds_hmap);
    if( err == 0) {
        lslogging_log_message( "md2cmds_worker: hsearch_r
            failed. theCmd = '%s' from string '%s'", theCmd, md2cmds_cmd);
        md2cmds_cmd[0] = 0;
        continue;
    }
    lslogging_log_message( "md2cmds_worker: Found command
        '%s'", theCmd);
    if( hrtnval != NULL) {
        cmdp = (md2cmds_cmd_kv_t *)hrtnval;
        err = cmdp->v( md2cmds_cmd);
        if( err) {
            lslogging_log_message( "md2cmds_worker: Command
                failed: '%s'", md2cmds_cmd);
            //
            // At this point we'd clear the queue but the queue is currently too
            // short to bother doing that
            //
        }
    }

    md2cmds_cmd[0] = 0;
}
}

```

7.9.4 Variable Documentation

7.9.4.1 double md2cmds_capz_moving_time = NAN [static]

Definition at line 32 of file md2cmds.c.

7.9.4.2 char md2cmds_cmd[MD2CMDS_CMD_LENGTH]

our command;

Definition at line 24 of file md2cmds.c.

7.9.4.3 md2cmds_cmd_kv_t md2cmds_cmd_kvs[] [static]

Initial value:

```
= {
  { "abort",          md2cmds_abort},
  { "center",         md2cmds_center},
  { "changeMode",     md2cmds_phase_change},
  { "collect",        md2cmds_collect},
  { "moveAbs",        md2cmds_moveAbs},
  { "moveRel",        md2cmds_moveRel},
  { "rotate",         md2cmds_rotate},
  { "run",            md2cmds_run_cmd},
  { "test",           md2cmds_test},
  { "set",            md2cmds_set},
  { "settransferpoint", md2cmds_settransferpoint},
  { "transfer",       md2cmds_transfer}
}
```

Definition at line 57 of file md2cmds.c.

7.9.4.4 regex_t md2cmds_cmd_regex [static]

Definition at line 36 of file md2cmds.c.

7.9.4.5 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.

7.9.4.6 struct hsearch_data md2cmds_hmap [static]

Definition at line 34 of file md2cmds.c.

7.9.4.7 pthread_cond_t md2cmds_homing_cond

coordinate homing and homed

Definition at line 18 of file md2cmds.c.

7.9.4.8 int md2cmds_homing_count = 0

We've asked a motor to home.

Definition at line 17 of file md2cmds.c.

7.9.4.9 pthread_mutex_t md2cmds_homing_mutex

our mutex;

Definition at line 19 of file md2cmds.c.

7.9.4.10 `lsredis_obj_t* md2cmds_md_status_code`

Definition at line 26 of file md2cmds.c.

7.9.4.11 `pthread_cond_t md2cmds_moving_cond`

wait for command to have been dequeued and run
coordinate call and response

Definition at line 14 of file md2cmds.c.

7.9.4.12 `int md2cmds_moving_count = 0`

Definition at line 22 of file md2cmds.c.

7.9.4.13 `pthread_mutex_t md2cmds_moving_mutex`

message passing between md2cmds and pg

Definition at line 15 of file md2cmds.c.

7.9.4.14 `int md2cmds_moving_queue_wait = 0`

Definition at line 13 of file md2cmds.c.

7.9.4.15 `pthread_mutex_t md2cmds_mutex`

mutex for the condition

Definition at line 11 of file md2cmds.c.

7.9.4.16 `pthread_t md2cmds_thread` `[static]`

Definition at line 28 of file md2cmds.c.

7.9.4.17 `int rotating = 0` `[static]`

flag: when omega is in position after a rotate we want to re-home omega

Definition at line 30 of file md2cmds.c.

7.10 `mk_pgpmac_redis.py` File Reference**Namespaces**

- namespace [mk_pgpmac_redis](#)

Functions

- def [mk_pgpmac_redis.active_simulation](#)
- def [mk_pgpmac_redis.asis](#)

Variables

- list [mk_pgpmac_redis.head](#) sys.argv[1]
- list [mk_pgpmac_redis.pref_ini](#) sys.argv[2]
- list [mk_pgpmac_redis.hard_ini](#) sys.argv[3]
- dictionary [mk_pgpmac_redis.motor_dict](#)
- dictionary [mk_pgpmac_redis.hard_ini_fields](#)
- list [mk_pgpmac_redis.motor_field_lists](#)
- list [mk_pgpmac_redis.bi_list](#) ["CryoSwitch"]
- dictionary [mk_pgpmac_redis.motor_presets](#)
- list [mk_pgpmac_redis.zoom_settings](#)
- tuple [mk_pgpmac_redis.hi](#) [iniParser.iniParser](#)([hard_ini](#))
- list [mk_pgpmac_redis.v](#) [motor_dict\[m\]](#)
- string [mk_pgpmac_redis.f](#) "HSETNX"
- list [mk_pgpmac_redis.xlate](#) [hard_ini_fields\[k\]](#)
- tuple [mk_pgpmac_redis.pi](#) [iniParser.iniParser](#)([pref_ini](#))
- int [mk_pgpmac_redis.i](#) 0
- tuple [mk_pgpmac_redis.ppos](#) [pi.get](#)([section](#), [option](#))
- string [mk_pgpmac_redis.fnc](#) "HSETNX"
- tuple [mk_pgpmac_redis.b](#) [pi.get](#)([section](#), "LightIntensity")
- tuple [mk_pgpmac_redis.p](#) [pi.get](#)([section](#), "MotorPosition")
- tuple [mk_pgpmac_redis.x](#) [pi.get](#)([section](#), "ScaleX")
- tuple [mk_pgpmac_redis.y](#) [pi.get](#)([section](#), "ScaleY")

7.11 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 [stdinfd](#)
Handle input from the keyboard.
- static int [running](#) = 1

7.11.1 Detailed Description

Main for the pgpmac project.

Date

2012

Author

Keith Brister

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

7.11.2 Function Documentation

7.11.2.1 int main (int *argc*, char ** *argv*)

Our main routine.

< argument flags

Parameters

in	<i>argc</i>	Number of arguments
in	<i>argv</i>	Vector of argument strings

Definition at line 353 of file [pgpmac.c](#).

```
{  
  
    static struct pollfd fda[3];           // 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;  
  
            case 'm':  
                mvars=1;  
                break;  
        }  
    }  
}
```

Generated on Tue Feb 12 2013 08:37:13 for LS-CAT PGPMAC by Doxygen

```

    }

    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]);
            }
        }
    }
}
endwin();
return 0;
}

```

7.11.2.2 void pgpmac_printf (char * *fmt*, ...)

Terminal output routine ala printf.

Parameters

in	<i>fmt</i>	Printf style formating string
----	------------	-------------------------------

Definition at line 330 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);
}

```

7.11.2.3 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 unsigned int cmds_on = 0;
    int ch;

    for( ch=wgetch(term_input); ch != ERR && running; ch=wgetch(
        term_input)) {
        // wprintw( term_output, "%04x\n", ch);
        // wnoutrefresh( term_output);

        switch( ch) {
            case KEY_F(1):
            case KEY_F(2):
            case KEY_F(3):

```

```

        running = 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( NULL, 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( NULL, "%s", cmds);
        }
        memset( cmds, 0, sizeof(cmds));
        cmds_on = 0;
        break;

    default:
        if( ch >= 0x20 && ch <= 0x7e) {
            if( cmds_on < sizeof( cmds)-1) {
                cmds[cmds_on++] = ch;
                cmds[cmds_on] = 0;
            }
        }
        break;
}

if( running) {
    mvwprintw( term_input, 1, 1, "PMAC> %s", cmds);
    wclrtoeol( term_input);
    box( term_input, 0, 0);
    wnoutrefresh( term_input);
    doupdate();
}
}
}

```

7.11.3 Variable Documentation

7.11.3.1 pthread_mutex_t ncurses_mutex

allow more than one thread access to the screen

Definition at line 242 of file pgpmac.c.

7.11.3.2 int running = 1 [static]

Definition at line 249 of file pgpmac.c.

7.11.3.3 struct pollfd stdinfd [static]

Handle input from the keyboard.

Definition at line 248 of file pgpmac.c.

7.11.3.4 WINDOW* term_input

place to put the cursor

Definition at line 238 of file pgpmac.c.

7.11.3.5 WINDOW* term_output

place to print stuff out

Definition at line 237 of file pgpmac.c.

7.11.3.6 WINDOW* term_status

shutter, lamp, air, etc status

Definition at line 239 of file pgpmac.c.

7.11.3.7 WINDOW* term_status2

shutter, lamp, air, etc status

Definition at line 240 of file pgpmac.c.

7.12 pgpmac.h File Reference

Headers for the entire pgpmac project.

```
#include <stdint.h>
#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 [lspgQueryQueueStruct](#)
Store each query along with it's callback function.
- struct [lspg_waitcryo_struct](#)
- struct [lspg_getcurrentsampleid_struct](#)
- struct [lspg_demandairrights_struct](#)
- struct [lspg_getcenter_struct](#)
Storage for getcenter query Used for the md2 ROTATE command that generates the centering movies.
- struct [lspg_starttransfer_struct](#)
returns 1 if transfer can continue 0 to abort
- struct [lspg_nextsample_struct](#)
Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)
- 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 256`
Fixed length for event names: simplifies string handling.
- `#define LSPMAC_MAGIC_NUMBER 0x9700436`
- `#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 [lspgQueryQueueStruct](#) [lspg_query_queue_t](#)
Store each query along with it's callback function.
- typedef struct [lspg_waitcryo_struct](#) [lspg_waitcryo_t](#)
- typedef struct [lspg_getcurrentsampleid_struct](#) [lspg_getcurrentsampleid_t](#)
- typedef struct [lspg_demandairrights_struct](#) [lspg_demandairrights_t](#)
- 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_starttransfer_struct](#) [lspg_starttransfer_t](#)
returns 1 if transfer can continue 0 to abort
- typedef struct [lspg_nextsample_struct](#) [lspg_nextsample_t](#)
Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)
- 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)
- char ** [lspg_array2ptrs](#) (char *)
returns a null terminated list of strings parsed from postgresql array
- char ** [lsredis_get_string_array](#) ([lsredis_obj_t](#) *p)
- void [lspmac_SockSendDPLine](#) (char *, char *fmt,...)
prepare (queue up) a line to send the dpram ascii command interface
- [pmac_cmd_queue_t](#) * [lspmac_SockSendline](#) (char *, char *,...)
Send a one line command.
- [lsredis_obj_t](#) * [lsredis_get_obj](#) (char *,...)
- char * [lsredis_getstr](#) ([lsredis_obj_t](#) *p)
return a copy of the key's string value be sure to free the result
- void [PmacSockSendline](#) (char *s)
- unsigned int [lspg_nextsample_all](#) (int *err)
- char [lsredis_getc](#) ([lsredis_obj_t](#) *p)
- long int [lsredis_getl](#) ([lsredis_obj_t](#) *p)
- void [lsevents_add_listener](#) (char *, void(*cb)(char *))
Add a callback routine to listen for a specific event.
- void [lsevents_init](#) ()
Initialize this module.
- void [lsevents_remove_listener](#) (char *, void(*cb)(char *))
Remove a listener previously added with lsevents_add_listener.
- 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_preregister_event](#) (char *fmt,...)
- void [lslogging_init](#) ()
Initialize the lslogging objects.

- void [lslogging_log_message](#) (char *fmt,...)
The routine everyone will be talking about.
- void [lslogging_run](#) ()
Start up the worker thread.
- void [lspg_demandairrights_all](#) ()
do nothing until we get airrights
- void [lspg_getcenter_call](#) ()
Request a getcenter query.
- void [lspg_getcenter_done](#) ()
Done with getcenter query.
- void [lspg_getcenter_wait](#) ()
Wait for a getcenter query to return.
- void [lspg_getcurrentsampleid_wait_for_id](#) (unsigned int test)
- void [lspg_init](#) ()
Initialize the lspg module.
- void [lspg_nextshot_call](#) ()
Queue up a nextshot query.
- void [lspg_nextshot_done](#) ()
Called when the next shot query has been processed.
- void [lspg_nextshot_wait](#) ()
Wait for the next shot query to get processed.
- void [lspg_query_push](#) (void(*cb)([lspg_query_queue_t](#) *, PGresult *), char *fmt,...)
Place a query on the queue.
- 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_starttransfer_call](#) (unsigned int nextsample, int [sample_detected](#), double ax, double ay, double az, double horz, double vert, double esttime)
- void [lspg_starttransfer_done](#) ()
- void [lspg_starttransfer_wait](#) ()
- void [lspg_waitcryo_all](#) ()
no need to get fancy with the wait cryo command It should not return until the robot is almost ready for air rights
- void [lspg_waitcryo_cb](#) ([lspg_query_queue_t](#) *qqp, PGresult *pgr)
- void [lspg_zoom_lut_call](#) ()
- int [lspmac_getBIPosition](#) ([lspmac_bi_t](#) *)
get binary input value
- void [lspmac_home1_queue](#) ([lspmac_motor_t](#) *mp)
Home the motor.
- void [lspmac_home2_queue](#) ([lspmac_motor_t](#) *mp)
Second stage of homing.
- void [lspmac_abort](#) ()
abort motion and try to recover
- void [lspmac_init](#) (int, int)
Initialize this module.
- int [lspmac_jogabs_queue](#) ([lspmac_motor_t](#) *, double)
Use jog to move motor to requested position.
- int [lspmac_move_or_jog_abs_queue](#) ([lspmac_motor_t](#) *mp, double requested_position, int use_jo)
Move method for normal stepper and servo motor objects Returns non-zero on abort, zero if OK.
- int [lspmac_move_or_jog_preset_queue](#) ([lspmac_motor_t](#) *, char *, int)

- move using a preset value returns 0 on success, non-zero on error*
- void `lspmac_move_or_jog_queue` (`lspmac_motor_t *`, double, int)
- int `lspmac_move_preset_queue` (`lspmac_motor_t *mp`, char *preset_name)
- Move a given motor to one of its preset positions.*
- int `lspmac_moveabs_queue` (`lspmac_motor_t *`, double)
- Use coordinate system motion program, if available, to move motor to requested position.*
- int `lspmac_moveabs_wait` (`lspmac_motor_t *mp`, double timeout)
- Wait for motor to finish moving.*
- void `lspmac_run` ()
- Start up the lspmac thread.*
- void `lspmac_video_rotate` (double secs)
- Special motion program to collect centering video.*
- int `lsredis_cmpnstr` (`lsredis_obj_t *p`, char *s, int n)
- int `lsredis_cmpstr` (`lsredis_obj_t *p`, char *s)
- int `lsredis_find_preset` (char *base, char *preset_name, double *dval)
- Get the value of the given preset and return it in dval Returns 0 on error, non-zero on success;.*
- int `lsredis_getb` (`lsredis_obj_t *p`)
- double `lsredis_getd` (`lsredis_obj_t *p`)
- void `lsredis_init` (char *pub, char *re, char *head)
- Initialize this module, that is, set up the connections.*
- int `lsredis_regexec` (const regex_t *preg, `lsredis_obj_t *p`, size_t nmatch, regmatch_t *pmatch, int eflags)
- void `lsredis_run` ()
- void `lsredis_setstr` (`lsredis_obj_t *p`, char *fmt,...)
- Set the value and update redis.*
- void `lstimer_set_timer` (char *, int, unsigned long int, unsigned long int)
- Create a timer.*
- void `lstimer_unset_timer` (char *event)
- Unsets all timers for the given event.*
- void `lstimer_init` ()
- Initialize the timer list and pthread stuff.*
- void `lstimer_run` ()
- Start up our thread.*
- void `lsupdate_init` ()
- void `lsupdate_run` ()
- void `md2cmds_init` ()
- Initialize the md2cmds module.*
- void `md2cmds_run` ()
- Start up the thread.*
- void `pgpmac_printf` (char *fmt,...)
- Terminal output routine ala printf.*
- void `lstest_main` ()
- int `lspmac_est_move_time` (double *est_time, int *mmask, `lspmac_motor_t *mp_1`, int jog_1, char *preset_1, double end_point_1,...)
- Move the motors and estimate the time it'll take to finish the job.*
- int `lspmac_est_move_time_wait` (double move_time, int cmask, `lspmac_motor_t *mp_1`,...)
- wait for motion to stop returns non-zero if the wait timed out*
- void `lsredis_set_preset` (char *base, char *preset_name, double dval)
- set the given preset to the given value create a new preset if we can't find it*
- `lsredis_obj_t * _lsredis_get_obj` (char *key)
- Maybe add a new object Used internally for this module Must be called with lsredis_mutex locked.*
- `lspmac_motor_t * lspmac_find_motor_by_name` (char *name)
- int `lsredis_find_preset_index_by_position` (`lspmac_motor_t *mp`)

For the given motor object return the index of the current preset or -1 if we are not at a preset position.

- void [lspmac_SockSendDPControlChar](#) (char *event, char c)
use dgram ascii interface to send a control character
- int [lspmac_set_motion_flags](#) (int *mmaskp, [lspmac_motor_t](#) *mp_1,...)
Set the coordinate system motion flags (m5075) for the null terminated list of motors that we are planning on running a motion program with.
- void [lsredis_load_presets](#) (char *motor_name)
update the presets hash table for the named motor

Variables

- [lspg_waitcryo_t](#) [lspg_waitcryo](#)
signal the robot
- [lspg_getcurrentsampleid_t](#) [lspg_getcurrentsampleid](#)
our currentsample id
- [lspg_demandairrights_t](#) [lspg_demandairrights](#)
our demandairrights object
- [lspg_getcenter_t](#) [lspg_getcenter](#)
the getcenter object
- [lspg_starttransfer_t](#) [lspg_starttransfer](#)
start a sample transfer
- [lspg_nextsample_t](#) [lspg_nextsample](#)
the very next sample
- [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 * smart_mag_oo`
Smart Magnet on/off.
- `lspmac_motor_t * blight_ud`
Back light Up/Down actuator.
- `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_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.
- `int lspmac_nmotors`
The number of motors we manage.
- `lspmac_bi_t * lp_air`
Low pressure air OK.
- `lspmac_bi_t * hp_air`
High pressure air OK.
- `lspmac_bi_t * cryo_switch`
that little toggle switch for the cryo
- `lspmac_bi_t * blight_down`
Backlight is down.
- `lspmac_bi_t * blight_up`
Backlight is up.
- `lspmac_bi_t * cryo_back`
cryo is in the back position
- `lspmac_bi_t * fluor_back`
fluor is in the back position
- `lspmac_bi_t * sample_detected`
smart magnet detected sample
- `lspmac_bi_t * etel_ready`
ETEL is ready.
- `lspmac_bi_t * etel_on`

- *ETEL is on.*
- `lspmac_bi_t * etel_init_ok`
- *ETEL initialized OK.*
- `lspmac_bi_t * minikappa_ok`
- *Minikappa is OK (whatever that means)*
- `lspmac_bi_t * smart_mag_on`
- *smart magnet is on*
- `lspmac_bi_t * arm_parked`
- *(whose arm? parked where?)*
- `lspmac_bi_t * shutter_open`
- *shutter is open (note in pmc says this is a slow input)*
- `lspmac_bi_t * smart_mag_off`
- *smart magnet is off*
- `lspmac_bi_t * smart_mag_err`
- *smart magnet error (coil broken perhaps)*
- `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;
- lsredis_obj_t * [md2cmds_md_status_code](#)
- pthread_mutex_t [lsredis_mutex](#)
- pthread_cond_t [lsredis_cond](#)
- int [lsredis_running](#)

7.12.1 Detailed Description

Headers for the entire pgpmac project.

Date

2012

Author

Keith Brister

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Definition in file [pgpmac.h](#).

7.12.2 Macro Definition Documentation

7.12.2.1 #define _GNU_SOURCE

Definition at line 7 of file pgpmac.h.

7.12.2.2 #define LS_DISPLAY_WINDOW_HEIGHT 8

Number of status box rows.

Definition at line 57 of file pgpmac.h.

7.12.2.3 #define LS_DISPLAY_WINDOW_WIDTH 24

Number of status box columns.

Definition at line 61 of file pgpmac.h.

7.12.2.4 #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 64 of file pgpmac.h.

7.12.2.5 #define LSEVENTS_EVENT_LENGTH 256

Fixed length for event names: simplifies string handling.

Definition at line 67 of file pgpmac.h.

7.12.2.6 `#define LSPMAC_MAGIC_NUMBER 0x9700436`

Definition at line 95 of file pgpmac.h.

7.12.2.7 `#define MD2CMDS_CMD_LENGTH 32`

Definition at line 488 of file pgpmac.h.

7.12.3 Typedef Documentation

7.12.3.1 `typedef struct lspg_demandairrights_struct lspg_demandairrights_t`

7.12.3.2 `typedef struct lspg_getcenter_struct lspg_getcenter_t`

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

7.12.3.3 `typedef struct lspg_getcurrentsampleid_struct lspg_getcurrentsampleid_t`

7.12.3.4 `typedef struct lspg_nextsample_struct lspg_nextsample_t`

Returns the next sample number Just a 32 bit int (Ha!, take that, nextshot!)

7.12.3.5 `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!)

7.12.3.6 `typedef struct lspgQueryQueueStruct lspg_query_queue_t`

Store each query along with it's callback function.

All calls are asynchronous

7.12.3.7 `typedef struct lspg_starttransfer_struct lspg_starttransfer_t`

returns 1 if transfer can continue 0 to abort

7.12.3.8 `typedef struct lspg_waitcryo_struct lspg_waitcryo_t`

7.12.3.9 `typedef struct lspmac_bi_struct lspmac_bi_t`

Storage for binary inputs.

7.12.3.10 `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.

7.12.3.11 typedef struct lsredis_obj_struct lsredis_obj_t

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

7.12.3.12 typedef struct lspmac_cmd_queue_struct pmac_cmd_queue_t

PMAC command queue item.

Command queue items are fixed length to simplify memory management.

7.12.3.13 typedef struct tagEthernetCmd pmac_cmd_t

PMAC ethernet packet definition.

Taken directly from the Delta Tau documentation.

7.12.4 Function Documentation

7.12.4.1 lsredis_obj_t* lsredis_get_obj(char * key)

Maybe add a new object Used internally for this module Must be called with lsredis_mutex locked.

Definition at line 505 of file lsredis.c.

```

{
    lsredis_obj_t *p;
    regmatch_t pmatch[2];
    int err;
    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;
    }

    // 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 ) {
        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 = strdup( 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 (events_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);
}

//
// 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;
}
//
// We arrive here with the valid flag lowered.  Go ahead and request the
// latest value.
//
redisAsyncCommand( roac, lsredis_hgetCB, p, "HGET %s VALUE"
    , key);

return p;
}

```

7.12.4.2 void lsevents_add_listener(char *raw_regexp, void (*)(char *) cb)

Add a callback routine to listen for a specific event.

Parameters

<i>raw_regexp</i>	String value of regular expression to listen to
<i>cb</i>	the routine to call

Definition at line 99 of file lsevents.c.

```

{
    lsevents_listener_t    *new;
    lsevents_event_names_t *enp;
    lsevents_callbacks_t   *cbp;
    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, raw_regexp, 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( raw_regexp);
new->cb = cb;

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

for( enp = lsevents_event_names; enp != NULL; enp = enp->
    next) {
    if( regexec( &new->re, enp->event, 0, NULL, 0) == 0) {
        cbp = calloc( 1, sizeof( lsevents_callbacks_t))
            ;
        cbp->cb = cb;
        cbp->next = enp->cbl;
        enp->cbl = cbp;
    }
}

pthread_mutex_unlock( &lsevents_listener_mutex);

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

```

7.12.4.3 void lsevents_init ()

Initialize this module.

Definition at line 373 of file lsevents.c.

```

{
    pthread_mutexattr_t mutex_initializer;

    // Use recursive mutexs
    //
    pthread_mutexattr_init( &mutex_initializer);
    pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

    pthread_mutex_init( &lsevents_queue_mutex, &
        mutex_initializer);
    pthread_cond_init( &lsevents_queue_cond, NULL);
    pthread_mutex_init( &lsevents_listener_mutex, &
        mutex_initializer);

    hcreate_r( 2*lsevents_max_events, &lsevents_event_name_ht
        );
}

```

7.12.4.4 void lsevents_preregister_event (char * fmt, ...)

Definition at line 314 of file lsevents.c.

```

{
    char s[128];
    va_list arg_ptr;

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

    lsevents_register_event( s);
}

```

7.12.4.5 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 (possibly a regular expression string)
<i>cb</i>	The callback routine to remove

Definition at line 157 of file lsevents.c.

```

{

lsevents_listener_t *last, *current;
lsevents_event_names_t *enp;
lsevents_callbacks_t *cbp, *last_cbp;

//
// 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;
    }
    last = current;
}

if( current == NULL) {
    lslogging_log_message( "lsevents_remove_listener:
        Could not find this listener for event '%s'", event);
    pthread_mutex_unlock( &lsevents_listener_mutex);
    return;
}

//
// Remove callback from lists of event names
//
for( enp = lsevents_event_names; enp != NULL; enp = enp->
    next) {
    if( regexec( &current->re, enp->event, 0, NULL, 0) == 0) {
        last_cbp = NULL;
        for( cbp = enp->cb1; cbp != NULL; cbp = cbp->next) {
            if( cbp->cb == cb) {
                if( last_cbp == NULL)
                    enp->cb1 = NULL;
                else
                    last_cbp->next = cbp->next;
                free( cbp);
                break;
            }
        }
    }
}

pthread_mutex_unlock( &lsevents_listener_mutex);

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

```

7.12.4.6 void lsevents_run ()

Start up the thread and get out of the way.

Definition at line 390 of file lsevents.c.

```

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

```

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

Call the callback routines for the given event.

Parameters

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

Definition at line 73 of file lsevents.c.

```

    {
        char event[LSEVENTS_EVENT_LENGTH];
        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);

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

        lsevents_queue[(lsevents_queue_on++) %
            LSEVENTS_QUEUE_LENGTH].evp = strdup(event);

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

```

7.12.4.8 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");
    }

```

7.12.4.9 void lslogging_log_message (char * fmt, ...)

The routine everyone will be talking about.

Parameters

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

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);
    vsnprintf( 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);
}

```

7.12.4.10 void lslogging_run ()

Start up the worker thread.

Definition at line 114 of file lslogging.c.

```

{
    pthread_create( &lslogging_thread, NULL, &lslogging_worker
        , NULL);
    lslogging_log_message( "Start up");
    lsevents_add_listener( ".+", lslogging_event_cb
        );
}

```

7.12.4.11 char** lspg_array2ptrs (char *)

returns a null terminated list of strings parsed from postgresql array

Definition at line 160 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] != '{' || a[strlen(a)-1] != '}' )
        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) {
    lslogging_log_message( "lspg_array2ptrs: out of memory
(acums)");
    exit( 1);
}

//
// allocate storage for the pointer array and the null terminator
//
rtn = (char **)calloc( n+1, sizeof( char *));
if( rtn == NULL) {
    lslogging_log_message( "lspg_array2ptrs: out of memory
(rtn)");
    exit( 1);
}
rtni = 0;

// Go through and create the individual strings
sp = acums;
*sp = 0;

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;
                free( acums);
                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.
// Through out the last entry since this there is not resonable expectation
// that

```



```

// we should be parsing it anyway.
//
rtn[rtni] = NULL;
free( acums);
return( rtn);
}

```

7.12.4.12 void lspg_demandairrights_all ()

do nothing until we get airrights

Definition at line 655 of file lspg.c.

```

{
    lspg_demandairrights_call();
    lspg_demandairrights_wait();
    // there is no "done" version
}

```

7.12.4.13 void lspg_getcenter_call ()

Request a getcenter query.

Definition at line 1276 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()");
}

```

7.12.4.14 void lspg_getcenter_done ()

Done with getcenter query.

Definition at line 1294 of file lspg.c.

```

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

```

7.12.4.15 void lspg_getcenter_wait ()

Wait for a getcenter query to return.

Definition at line 1286 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));
}

```

7.12.4.16 void lspg_getcurrentsampleid_wait_for_id (unsigned int test)

Definition at line 492 of file lspg.c.

```

pthread_mutex_lock( &lspg_getcurrentsampleid.mutex
);
while( lspg_getcurrentsampleid.getcurrentsampleid
!= test)
    pthread_cond_wait( &lspg_getcurrentsampleid.cond
, &lspg_getcurrentsampleid.mutex);

pthread_mutex_unlock( &lspg_getcurrentsampleid.mutex
);
}

```

7.12.4.17 void lspg_init ()

Initialize the lspg module.

Definition at line 1951 of file lspg.c.

```

{
pthread_mutex_init( &lspg_queue_mutex, NULL);
pthread_cond_init( &lspg_queue_cond, NULL);

lspg_demandairrights_init();
lspg_getcenter_init();
lspg_getcurrentsampleid_init();
lspg_lock_detector_init();
lspg_lock_diffractionmeter_init();
lspg_nextsample_init();
lspg_nextshot_init();
lspg_seq_run_prep_init();
lspg_starttransfer_init();
lspg_wait_for_detector_init();
lspg_waitcryo_init();
}

```

7.12.4.18 unsigned int lspg_nextsample_all (int * err)

Definition at line 567 of file lspg.c.

```

{
unsigned int rtn;

lspg_nextsample_call();
lspg_nextsample_wait();

if( lspg_nextsample.no_rows_returned) {
    rtn = 0;
    *err = 1;
} else {
    if( lspg_nextsample.nextsample_isnull) {
        rtn = 0;
        *err = 1;
    } else {
        rtn = lspg_nextsample.nextsample;
        *err = 0;
    }
}
lspg_nextsample_done();

return rtn;
}

```

7.12.4.19 void lspg_nextshot_call ()

Queue up a nextshot query.

Definition at line 923 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.nextshot2()");
}

```

7.12.4.20 void lspg_nextshot_done ()

Called when the next shot query has been processed.

Definition at line 941 of file lspg.c.

```

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

```

7.12.4.21 void lspg_nextshot_wait ()

Wait for the next shot query to get processed.

Definition at line 933 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));
}

```

7.12.4.22 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 127 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) %
    LS_PG_QUERY_QUEUE_LENGTH == lspg_query_queue_off %
    LS_PG_QUERY_QUEUE_LENGTH) {
    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);
};

```

7.12.4.23 void lspg_run ()

Start 'er runnin'.

Definition at line 1970 of file lspg.c.

```

{
    pthread_create( &lspg_thread, NULL, lspg_worker, NULL);
    lsevents_add_listener( "(appy|appz|capy|capz|scint) In
        Position", lspg_check_preset_in_position_cb
    );
    lsevents_add_listener( "(appy|appz|capy|capz|scint)
        Moving", lspg_unset_current_preset_moving_cb
    );
    lsevents_add_listener( "Preset Changed (.)",
        lspg_preset_changed_cb);
    lsevents_add_listener( "Sample (Detected|Absent)",
        lspg_sample_detector_cb);
    lsevents_add_listener( "Timer Update KVs",
        lspg_update_kvs_cb);
    lsevents_add_listener( "cam.zoom In Position",
        lspg_set_scale_cb);
    lstimer_set_timer( "Timer Update KVs", -1, 0, 500000000)
        ;
}

```

7.12.4.24 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 1194 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();
}

```

7.12.4.25 void lspg_starttransfer_call (unsigned int nextsample, int sample_detected, double ax, double ay, double az, double horz, double vert, double esttime)

Definition at line 401 of file lspg.c.

```

pthread_mutex_lock( &(lspg_starttransfer.mutex));
lspg_starttransfer.new_value_ready = 0;
pthread_mutex_unlock( &(lspg_starttransfer.mutex));

lspg_query_push( lspg_starttransfer.cb, "
    SELECT px.starttransfer( %d, %d, %.3f, %.3f, %.3f, %.3f, %.3f, %.3f",
        nextsample, sample_detected, ax, ay, az, horz
    , vert, esttime);
}

```

7.12.4.26 void lspg_starttransfer_done ()

Definition at line 416 of file lspg.c.

```

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

```

7.12.4.27 void lspg_starttransfer_wait ()

Definition at line 410 of file lspg.c.

```

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

```

7.12.4.28 void lspg_waitcryo_all ()

no need to get fancy with the wait cryo command It should not return until the robot is almost ready for air rights

Definition at line 606 of file lspg.c.

```

{
pthread_mutex_lock( &lspg_waitcryo.mutex);
lspg_waitcryo.new_value_ready = 0;

lspg_query_push( lspg_waitcryo.cb, "SELECT
    px.waitcryo()" );

while( lspg_waitcryo.new_value_ready == 0)
    pthread_cond_wait( &lspg_waitcryo.cond, &lspg_waitcryo
        .mutex);

pthread_mutex_unlock( &lspg_waitcryo.mutex);
}

```

7.12.4.29 void lspg_waitcryo_cb (lspg_query_queue_t * qqp, PGresult * pgr)

Definition at line 596 of file lspg.c.

```

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

```

7.12.4.30 void lspg_zoom_lut.call ()

7.12.4.31 void lspmac_abort ()

abort motion and try to recover

Definition at line 2031 of file lspmac.c.

```

    {
        //
        // Stop everything! (consider ^O instead of ^A)
        //
        lspmac_SockSendDPControlChar( "Abort Request", 0
            x01);

        //
        // and reset motion flag
        //
        lspmac_SockSendDPLine( "Reset", "%s", "M5075=0");
    }

```

7.12.4.32 int lspmac_est_move_time (double * est_time, int * mmaskp, lspmac_motor_t * mp_1, int jog_1, char * preset_1, double end_point_1, ...)

Move the motors and estimate the time it'll take to finish the job.

Returns the estimate time and the coordinate system mask to wait for

Parameters

<i>est_time</i>	Returns number of seconds we estimate the move(s) will take
<i>mmaskp</i>	Mask of coordinate systems we are trying to move, excluding jogs. Used to wait for motions to complete
<i>mp_1</i>	Pointer to first motor
<i>jog_1</i>	1 to force a jog, 0 to try a motion program DO NOT MIX JOGS AND MOTION PROGRAMS IN THE SAME COORDINATE SYSTEM!
<i>preset_1</i>	Name of preset we'd like to move to or NULL if end_point_1 should be used instead
<i>end_point_1</i>	End point for the first motor. Ignored if preset_1 is non null and identifies a valid preset for this motor
...	Perhaps more quads of motors, jog flags, preset names, and end points. End is a NULL motor pointer MUST END ARG LIST WITH NULL

< units to counts

< The total distance we need to go

< Our maximum velocity

< Our maximum acceleration

< Total time for this motor

< coordinate system motion flags

Definition at line 2737 of file lspmac.c.

```

    {
        static char axes[] = "XYZUVWABC";
        static int qs[9];
        static lspmac_combined_move_t motions[32];
        char s[256];
        int foundone;
        int moving_flags;
        struct timespec timeout;
        int j;
        va_list arg_ptr;
        lspmac_motor_t *mp;
    }

```

Generated on Tue Feb 12 2013 08:37:13 for LS-CAT PGPMAC by Doxygen

```

*      (1)      Tt = D/V  + V/A
*
*      When the distance is short, we need a different calculation:
*
*      D = 0.5 * A * T1^2  + 0.5 * A * T2^2  (T1 = acceleration time and
T2 = deceleration time)
*
*      or, since total time  Tt = T1 + T2 and T1 = T2,
*
*      D = A * (0.5*Tt)^2
*
*      or
*
*      (2)      Tt = 2 * sqrt( D/A)
*
*
*      When we accelerate to the maximum speed the time it takes is V/A so
the distance we travel (Da) is
*
*      Da = 0.5 * A * (V/A)^2
*
*      or
*
*      Da = 0.5 * V^2 / A
*
*      So when D > 2 * Da, or
*
*      D > V^2 / A
*
*      we need to use equation (1) otherwise we need to use equation (2)
*
*/

if( mp->magic != LSPMAC_MAGIC_NUMBER) {
    lslogging_log_message( "lspmac_est_move_time:
        WARNING: bad motor structure. Check that your motor list is NULL terminated.");
    break;
}

lslogging_log_message( "lspmac_est_move_time: find
    motor %s, jog %d, preset %s, endpoint %f",
        mp->name, jog, ps == NULL ? "NULL" : ps, ep);

Tt = 0.0;
if( mp != NULL && mp->max_speed != NULL && mp->max_accel
    != NULL && mp->u2c != NULL) {

    //
    // get the real endpoint if a preset was mentioned
    //
    if( ps != NULL && *ps != 0) {
        err = lsredis_find_preset( mp->name, ps, &
            maybe_ep);
        if( err != 0)
            ep = maybe_ep;
    }

    u2c = lsredis_getd( mp->u2c);

    if( u2c <= 0.0)
        continue;

    //
    // For look up tables user units are (or should be) counts and u2c should
    be 1
    //
    if( mp->nlut > 0 && mp->lut != NULL) {
        u2c = 1.0;
        D = lspmac_lut( mp->nlut, mp->lut, ep) - lspmac_lut
            ( mp->nlut, mp->lut, lspmac_getPosition( mp));
    } else {
        D = ep - lspmac_getPosition( mp);
    } // User units

    V = lsredis_getd( mp->max_speed) / u2c * 1000.;
    // User units per second
    A = lsredis_getd( mp->max_accel) / u2c * 1000. *
    1000; // User units per second per second

    neutral_pos = lsredis_getd( mp->neutral_pos);
    min_pos      = lsredis_getd( mp->min_pos) - neutral_pos
    ;
    max_pos      = lsredis_getd( mp->max_pos) - neutral_pos
    ;

```



```

if( ep < min_pos || ep > max_pos) {
    lslogging_log_message( "lspmac_est_move_time:
Motor %s Requested position %f out of range: min=%f, max=%f", mp->name, ep,
min_pos, max_pos);
    lsevents_send_event( "%s Move Aborted", mp->name
);
    return 1;
}

//
// Don't bother with motors without velocity or acceleration defined
//
if( V > 0.0 && A > 0.0) {
    if( fabs(D) > V*V/A) {
        //
        // Normal ramp up, constant velocity, and ramp down
        //
        Tt = fabs(D)/V + V/A;
    } else {
        //
        // Never reach constant velocity, just ramp up a bit and back down
        //
        Tt = 2.0 * sqrt( fabs(D)/A);
    }

    lslogging_log_message( "lspmac_est_move_time:
Motor: %s D: %f VV/A: %f Tt: %f", mp->name, D, V*V/A, Tt);
} else {
    //
    // TODO: insert move time based for DAC or BO motor like objects;
    // For now assume 100 msec;
    //
    Tt = 0.1;
}

// Perhaps flag a coordinate system
//
// We can move a motor that's not in a coordinate system but we cannot
move a motor that is but does not
// have an axis defined if we are also moving one that does. It's a
limitation, I guess.
//
if( jog != 1 &&
    mp->coord_num != NULL && lsredis_getl( mp->
coord_num) > 0 && lsredis_getl( mp->coord_num) <=
16 &&
    mp->motor_num != NULL && lsredis_getl( mp->
motor_num) > 0 && mp->axis != NULL && lsredis_getc( mp
->axis) != 0) {
    int axis;
    int motor_num;

    motor_num = lsredis_getl( mp->motor_num);

    axis = lsredis_getc( mp->axis);
    for( j=0; j<sizeof(axes); j++) {
        if( axis == axes[j])
            break;
    }

    if( j < sizeof( axes)) {
        //
        // Store the motion request for a normal PMAC motor
        //
        int cn;
        int in_position_band;

        cn = lsredis_getl( mp->coord_num);
        in_position_band = lsredis_getl( mp->in_position_band
);

        motions[motor_num - 1].coord_num = cn;
        motions[motor_num - 1].axis = j;
        motions[motor_num - 1].Delta = D * u2c;
        //
        // Don't ask to run a motion program if we are already where we want
to be
        //
        // Deadband is 10 counts except for zoom which is 100.
        // We use Ixx28 In-Position Band which has units of 1/16 count
        //
        //
        if( abs(motions[motor_num - 1].Delta)*16 >= in_position_band) {
            m5075 |= (1 << (cn - 1));
            motions[motor_num - 1].moveme = 1;
        }
    }
}

```

```

        lslogging_log_message( "lspmac_est_move_time:
moveme=%d motor '%s' motions index=%d coord_num=%d axis=%d Delta=%d m5075=%u",
                                motions[motor_num-1].moveme, mp->name,
motor_num -1, motions[motor_num-1].coord_num, motions[motor_num-1].axis
, motions[motor_num-1].Delta,
                                m5075);
    }
} else {
    //
    // Here we are dealling with a DAC or BO motor or just want to jog.
    //
    if( mp->jogAbs( mp, ep)) {
        lslogging_log_message( "lspmac_est_move_time:
motor %s failed to queue move of distance %f from %f", mp->name, D,
lspmac_getPosition(mp));
        lsevents_send_event( "Move Aborted");
        return 1;
    }
}
//
// Update the estimated time
//
*est_time = *est_time < Tt ? Tt : *est_time;

lslogging_log_message( "lspmac_est_move_time:
est_time=%f", *est_time);

}

mp = va_arg( arg_ptr, lspmac_motor_t *);
if( mp == NULL)
    break;

jog = va_arg( arg_ptr, int);
ps = va_arg( arg_ptr, char *);
ep = va_arg( arg_ptr, double);

}
va_end( arg_ptr);

// Set the motion program flags
//
if( m5075 != 0) {
    if( mmaskp != NULL)
        *mmaskp |= m5075; // Tell the caller about our new mask

    pthread_mutex_lock( &lspmac_moving_mutex);
    if( (lspmac_moving_flags & m5075) != m5075)
        lspmac_SockSendDPLine( NULL, "M5075=(M5075 | %d)",
m5075);

    clock_gettime( CLOCK_REALTIME, &timeout);
    //
    timeout.tv_sec += 2; // 2 seconds should be more than enough time to
        set the flags
    err = 0;
    while( err == 0 && (lspmac_moving_flags & m5075) !=
m5075)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
lspmac_moving_mutex, &timeout);
    moving_flags = lspmac_moving_flags;
    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "lspmac_est_move_time: Timed
out waiting for moving flags. lspmac_moving_flags = %0x", moving_flags);
        lsevents_send_event( "Combined Move Aborted");
        return 1;
    }
}

for( i=1; i<=16; i++) {
    //
    // Loop over coordinate systems
    //
    foundone = 0;

    for( j=0; j<9; j++)
        qs[j] = 0;

    for( j=0; j<31; j++) {
        //
        // Loop over motors

```

```

//
if( motions[j].moveme && motions[j].coord_num == i) {
    if( abs(motions[j].Delta) > 0) {
        qs[(int)(motions[j].axis)] = motions[j].Delta;
        foundone=1;
    }
}
}

if( foundone) {
    sprintf( s, "%d Q40=%d Q41=%d Q42=%d Q43=%d Q44=%d Q45=%d Q46=%d Q47=%d
        Q48=%d Q49=%d Q100=%d B180R",
        i, qs[0], qs[1], qs[2], qs[3], qs[4], qs[5], qs[6], qs[7], qs[8]
        , *est_time * 1000., 1 << (i-1));

    lspmac_SockSendDPLine( NULL, s);
}
}
return 0;
}

```

7.12.4.33 int lspmac_est_move_time_wait (double *move_time*, int *cmask*, lspmac_motor_t * *mp_1*, ...)

wait for motion to stop returns non-zero if the wait timed out

Parameters

<i>move_time</i>	The time out in seconds
<i>cmask</i>	A coordinate system mask to wait for
<i>mp_1</i>	NULL terminated list of individual motors to wait for

Both values are returned from lspmac_est_move_time

Definition at line 3084 of file lspmac.c.

```

{
    int err;
    double isecs, fsecs;
    struct timespec timeout;
    va_list arg_ptr;
    lspmac_motor_t *mp;

    clock_gettime( CLOCK_REALTIME, &timeout);
    fsecs = modf( move_time, &isecs);
    timeout.tv_sec += (long)floor(isecs);
    timeout.tv_nsec += (long)floor(fsecs * 1.e9);
    timeout.tv_sec += timeout.tv_nsec / 1000000000;
    timeout.tv_nsec %= 1000000000;

    err = 0;
    pthread_mutex_lock( &lspmac_moving_mutex);
    while( err == 0 && (lspmac_moving_flags & cmask) != 0)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
            lspmac_moving_mutex, &timeout);
    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err != 0) {
        if( err == ETIMEDOUT) {
            lslogging_log_message( "
                lctest_lspmac_est_move_time_wait: timed out waiting %f seconds, cmask = 0x%0x", move_time, cmask);
            lspmac_abort();
            return 1;
        }
    }

    va_start( arg_ptr, mp_1);
    for( mp = mp_1; mp != NULL; mp = va_arg( arg_ptr, lspmac_motor_t
        *)) {
        if( mp->magic != LSPMAC_MAGIC_NUMBER) {
            lslogging_log_message( "lspmac_est_move_time_wait:
                WARNING: motor list must be NULL terminated. Check your call to
                lspmac_est_move_time_wait.");
        }

        if( lspmac_moveabs_wait( mp, move_time)) {
            lslogging_log_message( "lspmac_est_move_time_wait:

```

```

        timed out waiting %f seconds for motor %s", move_time, mp->name);
    return 1;
}
}
va_end( arg_ptr);

return 0;
}

```

7.12.4.34 lspmac_motor_t* lspmac.find_motor_by_name (char * name)

Definition at line 4154 of file lspmac.c.

```

{
    lspmac_motor_t *rtn;
    ENTRY entry_in, *entry_outp;
    int err;

    entry_in.key = name;
    entry_in.data = NULL;
    err = hsearch_r( entry_in, FIND, &entry_outp, &motors_ht);
    if( err == 0) {
        lslogging_log_message( "lspmac.find_motor_by_name:
            hsearch_r failed for motor '%s': %s", name, strerror( errno));
        return NULL;
    }
    rtn = entry_outp->data;

    return rtn;
}

```

7.12.4.35 int lspmac.getBIPosition (lspmac_bi_t *)

get binary input value

Definition at line 1598 of file lspmac.c.

```

{
    int rtn;
    pthread_mutex_lock( &bip->mutex);
    rtn = bip->position;
    pthread_mutex_unlock( &bip->mutex);
    return rtn;
}

```

7.12.4.36 double lspmac.getPosition (lspmac_motor_t * mp)

get the motor position (with locking)

Parameters

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

Definition at line 1355 of file lspmac.c.

```

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

```

7.12.4.37 void lspmac_home1_queue (lspmac_motor_t * mp)

Home the motor.

Parameters

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

Definition at line 1221 of file lspmac.c.

```

{
    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. TODO (hint hint)
    //
    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) {
                int nogo;
                nogo = 0;
                pthread_mutex_lock( &(lspmac_motors[i].mutex));
                //
                // Don't go on if
                //
                // we are homing          or          ( not in position
                while      in open loop)
                //
                if( lspmac_motors[i].homing || ((lspmac_motors
                    [i].status2 & 0x01)==0) && ((lspmac_motors[i].status1 & 0x040000)
                    != 0)))
                    nogo = 1;
                pthread_mutex_unlock( &(lspmac_motors[i].mutex));
                if( nogo) {
                    pthread_mutex_unlock( &(mp->mutex));
                    return;
                }
            }
        }
    }
    mp->homing = 1;
    mp->not_done = 1; // set up waiting for cond
    mp->motion_seen = 0;
    // 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) {
    lspmac_SockSendDPline( mp->name, "##d$*",
        motor_num);
}

pthread_mutex_unlock( &(mp->mutex));

lsevents_send_event( "%s Homing", mp->name);
}

```

7.12.4.38 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 1309 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_SockSendDPline( mp->name, *spp);
}

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

```

7.12.4.39 void lspmac_init(int , int)

Initialize this module.

Definition at line 3671 of file lspmac.c.

```

    {
int i;
int err;
ENTRY entry_in, *entry_outp;
md2_status_t *p;
pthread_mutexattr_t mutex_initializer;

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

// Use recursive mutexs
//
pthread_mutexattr_init( &mutex_initializer);
pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

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

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

//
// 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 X", "omega",
lspmac_moveabs_queue, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, 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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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, lspmac_jogabs_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);

smart_mag_oo = lspmac_bo_init( &(lspmac_motors
[19]), "smartMagnet", "M1100=%d", &(md2_status.acc11c_5), 0x01)
;
blight_ud = lspmac_bo_init( &(lspmac_motors
[20]), "backLight", "M1101=%d", &(md2_status.acc11c_5), 0x02)
;
cryo = lspmac_bo_init( &(lspmac_motors
[21]), "cryo", "M1102=%d", &(md2_status.acc11c_5), 0x04)
;
dryer = lspmac_bo_init( &(lspmac_motors
[22]), "dryer", "M1103=%d", &(md2_status.acc11c_5), 0x08)
;
fluor = lspmac_bo_init( &(lspmac_motors
[23]), "fluor", "M1104=%d", &(md2_status.acc11c_5), 0x10)
;
flight_oo = lspmac_soft_motor_init( &(
lspmac_motors[24]), "frontLight",
lspmac_moveabs_frontlight_oo_queue);
blight_f = lspmac_soft_motor_init( &(
lspmac_motors[25]), "backLight.factor",
lspmac_moveabs_blight_factor_queue);
flight_f = lspmac_soft_motor_init( &(
lspmac_motors[26]), "frontLight.factor",
lspmac_moveabs_flight_factor_queue);

lp_air = lspmac_bi_init( &(lspmac_bis[
0]), &(md2_status.acc11c_1), 0x01, "Low Pressure Air OK", "
Low Pressure Air Failed");
hp_air = lspmac_bi_init( &(lspmac_bis[
1]), &(md2_status.acc11c_1), 0x02, "High Pressure Air OK", "
High Pressure Air Failed");
cryo_switch = lspmac_bi_init( &(lspmac_bis
[ 2]), &(md2_status.acc11c_1), 0x04, "CryoSwitchChanged",
"CryoSwitchChanged");
blight_down = lspmac_bi_init( &(lspmac_bis
[ 3]), &(md2_status.acc11c_1), 0x08, "Backlight Down",
"Backlight Not Down");
blight_up = lspmac_bi_init( &(lspmac_bis
[ 4]), &(md2_status.acc11c_1), 0x10, "Backlight Up",
"Backlight Not Up");
cryo_back = lspmac_bi_init( &(lspmac_bis
[ 5]), &(md2_status.acc11c_1), 0x40, "Cryo Back",
"Cryo Not Back");
fluor_back = lspmac_bi_init( &(lspmac_bis
[ 6]), &(md2_status.acc11c_2), 0x01, "Fluor. Det. Parked",
"Fluor. Det. Not Parked");
sample_detected = lspmac_bi_init( &(lspmac_bis
[ 7]), &(md2_status.acc11c_2), 0x02, "SamplePresent",
"SampleAbsent");
etel_ready = lspmac_bi_init( &(lspmac_bis
[ 8]), &(md2_status.acc11c_2), 0x20, "ETEL Ready",
"ETEL Not Ready");
etel_on = lspmac_bi_init( &(lspmac_bis
[ 9]), &(md2_status.acc11c_2), 0x40, "ETEL On",
"ETEL Off");
etel_init_ok = lspmac_bi_init( &(lspmac_bis

```



```

    [10]), &(md2_status.accl1c_2), 0x80, "ETEL Init OK",
    "ETEL Init Not OK");
minikappa_ok = lspmac_bi_init( &(lspmac_bis
    [11]), &(md2_status.accl1c_3), 0x01, "Minikappa OK",
    "Minikappa Not OK");
smart_mag_on = lspmac_bi_init( &(lspmac_bis
    [12]), &(md2_status.accl1c_3), 0x04, "Smart Magnet On",
    "Smart Magnet Not On");
arm_parked = lspmac_bi_init( &(lspmac_bis
    [13]), &(md2_status.accl1c_3), 0x08, "Arm Parked",
    "Arm Not Parked");
smart_mag_err = lspmac_bi_init( &(lspmac_bis
    [14]), &(md2_status.accl1c_3), 0x10, "Smart Magnet Error",
    "Smart Magnet OK");
shutter_open = lspmac_bi_init( &(lspmac_bis
    [15]), &(md2_status.accl1c_3), 0x100, "Shutter Open",
    "Shutter Not Open");
smart_mag_off = lspmac_bi_init( &(lspmac_bis
    [16]), &(md2_status.accl1c_5), 0x01, "Smart Magnet Off",
    "Smart Magnet Not Off");

// Set up hash table
//
err = hcreate_r( LSPMAC_MAX_MOTORS * 2, &motors_ht)
;
if( err == 0) {
    lslogging_log_message( "lspmac_init: hcreate_r failed:
        '%s'", strerror( errno));
    exit( -1);
}
for( i=0; i<lspmac_nmotors; i++) {
    entry_in.key = lspmac_motors[i].name;
    entry_in.data = &(lspmac_motors[i]);
    err = hsearch_r( entry_in, ENTER, &entry_outp, &motors_ht);
    if( err == 0) {
        lslogging_log_message( "lspmac_init: hsearch_r
            failed for motor %s: '%s'", lspmac_motors[i].name, strerror( errno));
        exit( -1);
    }
}

//
// 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, &mutex_initializer);
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, &
    mutex_initializer);
pthread_cond_init( &lspmac_shutter_cond, NULL);
pmacfd.fd = -1;

pthread_mutex_init( &lspmac_moving_mutex, &
    mutex_initializer);
pthread_cond_init( &lspmac_moving_cond, NULL);

```

```

pthread_mutex_init( &lspmac_ascii_mutex, &mutex_initializer
);

pthread_mutex_init( &lspmac_ascii_buffers_mutex, &
mutex_initializer);

//
// clear the ascii communications buffers
//
{
    uint32_t cc;
    cc = 0;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
, 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);

    cc = 0x18;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
, 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);
}

lspmac_SockSendDPLine( NULL, "I5=0");
lspmac_SockSendDPLine( NULL, "ENABLE PLCC 0,2");
lspmac_SockSendDPLine( NULL, "DISABLE PLCC 1");
lspmac_SockSendDPLine( NULL, "I5=3");

lsevents_preregister_event( "omega crossed zero");
lsevents_preregister_event( "Move Aborted");
lsevents_preregister_event( "Combined Move Aborted"
);

for( i=1; i<=16; i++) {
    lsevents_preregister_event( "Coordsys %d Stopped"
, i);
}
}

```

7.12.4.40 int lspmac_jogabs_queue(lspmac_motor_t *, double)

Use jog to move motor to requested position.

Definition at line 3383 of file lspmac.c.

```

{

return lspmac_move_or_jog_abs_queue( mp,
requested_position, 1);
}

```

7.12.4.41 int lspmac_move_or_jog_abs_queue(lspmac_motor_t * mp, double requested_position, int use_jo)

Move method for normal stepper and servo motor objects Returns non-zero on abort, zero if OK.

< format string for coordinate system move

< 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_jo</i>	1 to force jog, 0 for motion prog

Definition at line 3135 of file lspmac.c.

```

    {
        char *fmt;
        int q100;
        int requested_pos_cnts;
        int coord_num, motor_num;
        char *axis;
        double u2c;
        double neutral_pos;
        double min_pos, max_pos;
        int pos_limit_hit, neg_limit_hit, in_position_band;
        struct timespec timeout, now;
        int err;

        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);
        neutral_pos  = lsredis_getd( mp->neutral_pos);
        min_pos      = lsredis_getd( mp->min_pos) -
            neutral_pos;
        max_pos      = lsredis_getd( mp->max_pos) -
            neutral_pos;
        pos_limit_hit = lsredis_getd( mp->pos_limit_hit
        );
        neg_limit_hit = lsredis_getd( mp->neg_limit_hit
        );
        in_position_band = lsredis_getl( mp->in_position_band
        );

        if( u2c == 0.0 || requested_position < min_pos || requested_position >
            max_pos) {
            //
            // Shouldn't try moving a motor that's in trouble
            //
            pthread_mutex_unlock( &(mp->mutex));
            lslogging_log_message( "lspmac_move_or_jog_abs_queue:
                %s u2c=%f requested position=%f min allowed=%f max allowed=%f", mp->name
                , u2c, requested_position, min_pos, max_pos);
            lsevents_send_event( "%s Move Aborted", mp->name);
            return 1;
        }

        if( (neg_limit_hit && (requested_position < mp->position)) || (pos_limit_hit
            && (requested_position > mp->position))) {
            pthread_mutex_unlock( &(mp->mutex));
            lslogging_log_message( "lspmac_move_or_jog_abs_queue:
                %s Moving wrong way on limit: requested position=%f current position=%f low
                limit=%d high limit=%d",
                mp->name, requested_position, mp->position
                , neg_limit_hit, pos_limit_hit);
            lsevents_send_event( "%s Move Aborted", mp->name);
            return 2;
        }

        mp->requested_position = requested_position;
        if( mp->nlut > 0 && mp->lut != NULL) {
            mp->requested_pos_cnts = lspmac_lut( mp->nlut
                , mp->lut, requested_position);
        } else {
            mp->requested_pos_cnts = u2c * (requested_position +
                neutral_pos);
        }
        requested_pos_cnts = mp->requested_pos_cnts;

        //
        // Bluff if we are already there
        //
        if( (abs( requested_pos_cnts - mp->actual_pos_cnts) * 16 <
            in_position_band) || (lsredis_getb( mp->active) != 1)) {
            //
            // Lie and say we moved even though we didn't. Who will know? We are
            // within the deadband or not active.
            //
            mp->not_done      = 1;
            mp->motion_seen   = 0;
            mp->command_sent  = 0;

            lsevents_send_event( "%s Moving", mp->name);

            mp->not_done      = 0;
            mp->motion_seen   = 1;
            mp->command_sent  = 1;

```

```

    if( lsredis_getb( mp->active) != 1) {
        //
        // fake the motion for simulated motors
        //
        mp->position = requested_position;
        mp->actual_pos_cnts = requested_pos_cnts;
    }
    pthread_mutex_unlock( &(mp->mutex));

    lsevents_send_event( "%s In Position", mp->name);
    return 0;
}

mp->not_done      = 1;
mp->motion_seen   = 0;
mp->command_sent  = 0;

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) {
    //
    // Make sure the coordinate system is not moving something, wait if it is
    //
    pthread_mutex_lock( &lspmac_moving_mutex);

    clock_gettime( CLOCK_REALTIME, &now);
    //
    // TODO: Have all moves estimate how long they'll take and use that here
    //
    timeout.tv_sec = now.tv_sec + 60.0;           // a long timeout, but
    // we might really be moving something that takes this long (or longer)
    timeout.tv_nsec = now.tv_nsec;

    err = 0;
    while( err == 0 && (lspmac_moving_flags & q100) != 0)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
            lspmac_moving_mutex, &timeout);

    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "
            lspmac_move_or_jog_abs_queue: Timed Out.  lspmac_moving_flags = %0x", lspmac_moving_flags
        );
        lsevents_send_event( "%s Move Aborted", mp->name);
        return 1;
    }

    //
    // Set the "we are moving this coordinate system" flag
    //
    lspmac_SockSendDpline( NULL, "M5075=(M5075 | %d)",
        q100);

    switch( *axis) {
    case 'A':
        fmt = "%d Q16=%d Q100=%d B146R";
        break;

    case 'B':
        fmt = "%d Q17=%d Q100=%d B147R";
        break;

    case 'C':
        fmt = "%d Q18=%d Q100=%d B148R";
        break;
    case 'X':
        fmt = "%d Q10=%d Q100=%d B140R";
        break;

    case 'Y':
        fmt = "%d Q11=%d Q100=%d B141R";
        break;

    case 'Z':
        fmt = "%d Q12=%d Q100=%d B142R";
        break;
    }
}

```

```

    case 'U':
        fmt = "%d Q13=%d Q100=%d B143R";
        break;

    case 'V':
        fmt = "%d Q14=%d Q100=%d B144R";
        break;

    case 'W':
        fmt = "%d Q15=%d Q100=%d B145R";
        break;
}

//
// Make sure the flag has been seen
//

clock_gettime( CLOCK_REALTIME, &now);
timeout.tv_sec = now.tv_sec + 4.0; // also a long timeout.
    This should really only take a few milliseconds on a slow day
timeout.tv_nsec = now.tv_nsec;

pthread_mutex_lock( &lspmac_moving_mutex);

err = 0;
while( err == 0 && (lspmac_moving_flags & q100) == 0)
    err = pthread_cond_timedwait( &lspmac_moving_cond, &
        lspmac_moving_mutex, &timeout);
pthread_mutex_unlock( &lspmac_moving_mutex);

if( err == ETIMEDOUT) {
    lslogging_log_message( "
    lspmac_move_or_jog_abs_queue: Did not see flag propagate. Move aborted.");
    lsevents_send_event( "%s Move Aborted", mp->name);
    return 1;
}
}

pthread_mutex_lock( &(mp->mutex));
if( use_jog) {
    lspmac_SockSendDPLine( mp->name, "#%d j=%d",
        motor_num, requested_pos_cnts);
} else {
    lspmac_SockSendDPLine( mp->name, fmt, coord_num,
        requested_pos_cnts, q100);
}
pthread_mutex_unlock( &(mp->mutex));

free( axis);

return 0;
}

```

7.12.4.42 int lspmac_move_or_jog_preset.queue(lspmac_motor_t*, char*, int)

move using a preset value returns 0 on success, non-zero on error

Definition at line 3344 of file lspmac.c.

```

{
double pos;
int err;
int rtn;

if( preset == NULL || *preset == 0) {
    lsevents_send_event( "%s Move Aborted", mp->name);
    return 0;
}

err = lsredis_find_preset( mp->name, preset, &pos);

if( err != 0)
    rtn = lspmac_move_or_jog_abs_queue( mp, pos,
        use_jog);
else {
    lsevents_send_event( "%s Move Aborted", mp->name);
    rtn = 1;
}
return rtn;
}

```

7.12.4.43 void `lspmac_move_or_jog_queue (lspmac_motor_t *, double, int)`

7.12.4.44 int `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>preset_name</i>	Name of the preset to use

Definition at line 2396 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 1;

    err = mp->jogAbs( mp, pos);
    if( !err)
        lslogging_log_message( "lspmac_move_preset_queue:
            moving %s to preset '%s' (%f)", mp->name, preset_name, pos);
    //
    // the abort event should have been sent in moveAbs
    //
    return err;
}

```

7.12.4.45 int `lspmac_moveabs_queue (lspmac_motor_t *, double)`

Use coordinate system motion program, if available, to move motor to requested position.

Definition at line 3372 of file `lspmac.c`.

```

{
    return lspmac_move_or_jog_abs_queue( mp,
        requested_position, 0);
}

```

7.12.4.46 int `lspmac_moveabs_wait (lspmac_motor_t * mp, double timeout_secs)`

Wait for motor to finish moving.

Assume motion already queued, now just wait

Parameters

<i>mp</i>	The motor object to wait for
<i>timeout_secs</i>	The number of seconds to wait for. Fractional values fine.

Definition at line 3398 of file `lspmac.c`.

```

{
    struct timespec timeout, now;
    double isecs, fsecs;
    int err;
}

```

```

//
// Copy the queue item for the most recent move request
//
clock_gettime( CLOCK_REALTIME, &now);

fsecs = modf( timeout_secs, &isecs);

timeout.tv_sec = now.tv_sec + (long)floor( isecs);
timeout.tv_nsec = now.tv_nsec + (long)floor( fsecs * 1.0e9);

timeout.tv_sec += timeout.tv_nsec / 1000000000;
timeout.tv_nsec %= 1000000000;

err = 0;
pthread_mutex_lock( &(mp->mutex));

while( err == 0 && mp->command_sent == 0)
    err = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &timeout);
pthread_mutex_unlock( &(mp->mutex));
if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "lspmac_moveabs_wait:
unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
timeout.tv_nsec);
    }
    return 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.

err = 0;
pthread_mutex_lock( &(mp->mutex));
while( err == 0 && mp->motion_seen == 0)
    err = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &timeout)
;

if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "lspmac_moveabs_wait:
unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
timeout.tv_nsec);
    }
    pthread_mutex_unlock( &(mp->mutex));
    return 1;
}

//
// wait for the motion that we know has started to finish
//
err = 0;
while( err == 0 && mp->not_done)
    err = pthread_cond_timedwait( &(mp->cond), &(mp->mutex), &timeout)
;

if( err != 0) {
    if( err != ETIMEDOUT) {
        lslogging_log_message( "lspmac_moveabs_wait:
unexpected error from timedwait: %d tv_sec %ld tv_nsec %ld", err, timeout.tv_sec,
timeout.tv_nsec);
    }
    pthread_mutex_unlock( &(mp->mutex));
    return 1;
}

//
// 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));
return 0;
}

```

7.12.4.47 void lspmac_run ()

Start up the lspmac thread.

Definition at line 4202 of file lspmac.c.

```

        {
char **inits;
lspmac_motor_t *mp;
char evts[64];
int i;
int active;
int motor_num;

pthread_create( &pmac_thread, NULL, lspmac_worker,
    NULL);

lsevents_add_listener( "CryoSwitchChanged",
    lspmac_cryoSwitchChanged_cb);
lsevents_add_listener( "scint In Position",
    lspmac_scint_maybe_turn_on_dryer_cb);
lsevents_add_listener( "scint Moving",
    lspmac_scint_maybe_turn_off_dryer_cb);
lsevents_add_listener( "scint In Position",
    lspmac_scint_maybe_return_sample_cb);
lsevents_add_listener( "scint Moving",
    lspmac_scint_maybe_move_sample_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 Moving",
    lspmac_light_zoom_cb);

for( i=0; i<lspmac_nmotors; i++) {
    snprintf( evts, sizeof( evts)-1, "%s command accepted", lspmac_motors
        [i].name);
    evts[sizeof( evts)-1] = 0;
    lsevents_add_listener( evts, lspmac_command_done_cb
        );
}

lspmac_zoom_lut_setup();
lspmac_flight_lut_setup();
lspmac_blight_lut_setup();
lspmac_fscint_lut_setup();

//
// Clear the command interfaces
//
lspmac_SockSendControlCharPrint( NULL, '\x18')
    ;
{
    uint32_t cc;
    cc = 0;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);

    cc = 0x18;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
        , 0x0e9e, 0, 4, (char *)&cc, NULL, 1, NULL);
}

//
// 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_SockSendDPLine( NULL, *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);
    motor_num = lsredis_getl( mp->motor_num);

    if( motor_num >= 1 && motor_num <= 32) {

        //
        // Set the PMAC to be consistant with redis
        //
        lspmac_SockSendDPLine( NULL, "I%d16=%f I%d17=%f
            I%d28=%d", motor_num, lsredis_getd( mp->max_speed), motor_num,

```



```

    lsredis_getd( mp->max_accel), motor_num, lsredis_getl
    ( mp->in_position_band));
}

// 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->
    inactive_init);
    break;

default:
    lslogging_log_message( "lspmac_run: motor %s is
    neither active nor inactive (!?)", mp->name);
    inits = NULL;
}
if( inits != NULL) {
    while( *inits != NULL) {
        lspmac_SockSendDPLine( NULL, *inits);
        inits++;
    }
}
}
}

```

7.12.4.48 int lspmac_set_motion_flags (int *mmaskp, lspmac_motor_t *mp_1, ...)

Set the coordinate system motion flags (m5075) for the null terminated list of motors that we are planning on running a motion program with.

Note that lspmac_est_move_time already takes care of this, use when calling a motion program directly

Parameters

<i>mmaskp</i>	Returned value of the mask generated. Ignored if null.
<i>mp_1</i>	start of null terminated list of motors.

Definition at line 2651 of file lspmac.c.

```

{
    va_list arg_ptr;
    struct timespec timeout;
    int err;
    int cn;
    int need_flag;
    lspmac_motor_t *mp;
    int mask;

    mask = 0;
    if( maskp != NULL)
        *maskp = 0;

    if( mp_1==NULL)
        return 0;

    //
    // add the coordinate system flags to mask
    //
    va_start( arg_ptr, mp_1);
    for( mp = mp_1; mp!=NULL; mp = va_arg( arg_ptr, lspmac_motor_t
    *)) {
        if( mp->magic != LSPMAC_MAGIC_NUMBER) {
            lslogging_log_message( "lspmac_set_motion_flags:
            WARNING: motor list must be NULL terminated. Check your call to
            lspmac_set_motion_flags.");
            break;
        }
        cn = lsredis_getl( mp->coord_num);
        if( cn < 1 || cn > 16)

```

```

        continue;

        mmask |= 1 << (cn - 1);
    }
    va_end( arg_ptr);

    if( mmaskp != NULL)
        *mmaskp = mmask;

    //
    // It could be the flag is already what we want. We might set up a race
    // condition if we
    // try to set it again. (so don't)
    //
    pthread_mutex_lock( &lspmac_moving_mutex);

    if( (lspmac_moving_flags & mmask) != 0)
        need_flag = 0;
    else
        need_flag = 1;

    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( !need_flag)
        return 0;

    //
    // Set m5075 and make sure it propagates
    //
    lspmac_SockSendDPLine( NULL, "M5075=(M5075 | %d)", mmask
    );
    clock_gettime( CLOCK_REALTIME, &timeout);
    timeout.tv_sec += 2;

    err = 0;
    pthread_mutex_lock( &lspmac_moving_mutex);
    while( err == 0 && (lspmac_moving_flags & mmask) != mmask)
        err = pthread_cond_timedwait( &lspmac_moving_cond, &
        lspmac_moving_mutex, &timeout);

    pthread_mutex_unlock( &lspmac_moving_mutex);

    if( err == ETIMEDOUT) {
        lslogging_log_message( "lspmac_set_motion_flags: timed
        out waiting for motion %d flag to be set", mmask);
        return 1;
    }
    return 0;
}

```

7.12.4.49 void lspmac_SockSendDPControlChar (char * event, char c)

use dpram ascii interface to send a control character

Definition at line 1995 of file lspmac.c.

```

{
    uint16_t buff;

    buff = 0x07 & c;
    lspmac_send_command( VR_UPLOAD, VR_PMAC_SETMEM
    , 0x0e9e, 0, 2, (char *)&buff, lspmac_SockSendDPControlCharCB
    , 1, event);
    lsevents_send_event( "%s queued", event);
}

```

7.12.4.50 void lspmac_SockSendDPLine (char *, char * fmt, ...)

prepare (queue up) a line to send the dpram ascii command interface

Definition at line 1968 of file lspmac.c.

```

{
    va_list arg_ptr;
    uint32_t index;
    char *pl;

```

```

pthread_mutex_lock( &lspmac_ascii_mutex);
index = lspmac_dpascii_on++ % LSPMAC_DPASCII_QUEUE_LENGTH
;

pl = lspmac_dpascii_queue[index].pl;

va_start( arg_ptr, fmt);
vsnprintf( pl, 159, fmt, arg_ptr);
pl[159] = 0;
va_end( arg_ptr);

lspmac_dpascii_queue[index].event = event;

pthread_mutex_unlock( &lspmac_ascii_mutex);
}

```

7.12.4.51 `lspmac_cmd_queue_t* lspmac_SockSendline (char * event, char * fmt, ...)`

Send a one line command.

Uses printf style arguments.

Parameters

in	<i>event</i>	base name for events
in	<i>fmt</i>	Printf style format string

Definition at line 1076 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, event);
}

```

7.12.4.52 `void lspmac_video_rotate (double secs)`

Special motion program to collect centering video.

Definition at line 2613 of file `lspmac.c`.

```

{
double q10;           // starting position (counts)
double q11;           // delta counts
double q12;           // milliseconds to run over delta

double u2c;
double neutral_pos;

if( secs <= 0.0)
    return;

omega_zero_search = 1;

pthread_mutex_lock( &(omega->mutex));
u2c = lsredis_getd( omega->u2c);
neutral_pos = lsredis_getd( omega->neutral_pos);

q10 = neutral_pos * u2c;
q11 = 360.0 * u2c;
q12 = 1000 * secs;
}

```

```

    omega_zero_velocity = 360.0 * u2c / secs; //
        counts/second to back calculate zero crossing time

    lspmac_SockSendDPLine( omega->name, "&1
        Q10=%.1f Q11=%.1f Q12=%.1f Q13=(I117) Q14=(I116) B240R", q10, q11, q12);
    pthread_mutex_unlock( &(omega->mutex));
}

```

7.12.4.53 int lsredis_cmpnstr (lsredis_obj_t * p, char * s, int n)

Definition at line 253 of file lsredis.c.

```

{
    int rtn;
    pthread_mutex_lock( &p->mutex);
    while( p->valid == 0)
        pthread_cond_wait( &p->cond, &p->mutex);

    rtn = strncmp( p->value, s, n);
    pthread_mutex_unlock( &p->mutex);
    return rtn;
}

```

7.12.4.54 int lsredis_cmpstr (lsredis_obj_t * p, char * s)

Definition at line 242 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;
}

```

7.12.4.55 int lsredis_find_preset (char * base, char * preset_name, double * dval)

Get the value of the given preset and return it in dval Returns 0 on error, non-zero on success;.

Definition at line 898 of file lsredis.c.

```

{
    char s[512];
    int err;
    ENTRY entry_in, *entry_outp;
    lsredis_preset_list_t *pl;

    snprintf( s, sizeof( s)-1, "%s%s", motor_name, preset_name);
    s[sizeof(s)-1] = 0;

    entry_in.key = s;
    entry_in.data = NULL;
    err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
    );

    if( err == 0) {
        // not found (or some other problem that means we don't have an answer
        //
        // Maybe someone added a new preset and we don't know about it yet
        //
        lsredis_load_presets( motor_name);
        err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
        );
        if( err == 0) {
            //
            // Guess not. Give up. We tried
            //

```

```

        *dval = 0.0;
        return 0;
    }
}
p1 = entry_outp->data;
*dval = lsredis_getd( p1->position);
return 1;
}

```

7.12.4.56 int lsredis_find_preset_index_by_position (lspmac_motor_t * mp)

For the given motor object return the index of the current preset or -1 if we are not at a preset position.

Definition at line 980 of file lsredis.c.

```

{
    lsredis_obj_t *p;
    int plength;
    int i;
    double ur, pos;

    p = lsredis_get_obj( "%s.presets.length", mp->name);
    plength = lsredis_get_or_set_l( p, 0);

    if( plength <= 0) {
        return -1;
    }

    ur = lsredis_getd( mp->update_resolution);
    pos = lspmac_getPosition( mp);

    for( i=0; i<plength; i++) {
        p = lsredis_get_obj( "%s.presets.%d.position", mp->name,
            i);
        if( fabs( pos - lsredis_getd( p)) <= ur) {
            return i;
        }
    }
    return -1;
}

```

7.12.4.57 lsredis_obj_t* lsredis_get_obj(char *, ...)

Definition at line 591 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;

    pthread_mutex_lock( &lsredis_mutex);
    while( lsredis_running == 0)
        pthread_cond_wait( &lsredis_cond, &lsredis_mutex);

    rtn = _lsredis_get_obj( kp);
    pthread_mutex_unlock( &lsredis_mutex);

    free( kp);
}

```

```

    return rtn;
}

```

7.12.4.58 char** lsredis_get_string_array (lsredis_obj_t * p)

Definition at line 432 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;
}

```

7.12.4.59 int lsredis_getb (lsredis_obj_t * p)

Definition at line 445 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;
}

```

7.12.4.60 char lsredis_getc (lsredis_obj_t * p)

Definition at line 458 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;
}

```

7.12.4.61 double lsredis_getd (lsredis_obj_t * p)

Definition at line 381 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;
}

```

7.12.4.62 long int lsredis_getl (lsredis_obj_t * p)

Definition at line 394 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;
}

```

7.12.4.63 char* lsredis_getstr (lsredis_obj_t * p)

return a copy of the key's string value be sure to free the result

Definition at line 281 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;
}

```

7.12.4.64 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 1012 of file lsredis.c.

```

{
    int err;
    int nerrmsg;
    char *errmsg;

    //
    // set up hash map to store redis objects
    //
    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_cond_init( &lsredis_cond, 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);
wrac = redisAsyncConnect("127.0.0.1", 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;

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);
    }
}

hcreate_r( lsredis_preset_max_n * 2, &lsredis_preset_ht
    );
pthread_mutex_init( &lsredis_preset_list_mutex, NULL
    );
}

```

7.12.4.65 void lsredis_load_presets(char * motor_name)

update the presets hash table for the named motor

Definition at line 825 of file lsredis.c.

```

{
    lsredis_obj_t *p;
    lsredis_preset_list_t *pl;
    int plength;
    char *preset_name;
    int i;
    int key_length;
    ENTRY entry_in, *entry_outp;

    p = lsredis_get_obj( "%s.presets.length", motor_name);
    plength = lsredis_get_or_set_l( p, 0);

```



```

if( plength <= 0)
    return;

pthread_mutex_lock( &lsredis_preset_list_mutex);

for( i=0; i<plength; i++) {
    pl = calloc( 1, sizeof( lsredis_preset_list_t));
    pl->name = lsredis_get_obj( "%s.presets.%d.name",
        motor_name, i);
    pl->position = lsredis_get_obj( "
        %s.presets.%d.position", motor_name, i);
    pl->index = i;

    preset_name = lsredis_getstr( pl->name);
    key_length = strlen( motor_name) + strlen( preset_name) + 1;
    pl->key = calloc( key_length, 1);

    pl->next = lsredis_preset_list;
    lsredis_preset_list = pl;

    snprintf( pl->key, key_length, "%s%s", motor_name, preset_name);

    entry_in.key = pl->key;
    entry_in.data = pl;
    hsearch_r( entry_in, ENTER, &entry_outp, &lsredis_preset_ht
    );
    if( entry_outp->data != pl) {
        //
        // The key was already there or we couldn't add it
        //
        if( entry_outp->data == NULL)
            lslogging_log_message( "lsredis_load_presets:
            could not add preset '%s' for motor '%s'", preset_name, motor_name);

        free( pl->key);
        free( pl);
    } else {
        //
        // We've successfully added the new key
        //
        lsredis_preset_n++;
        //
        // Resize the hash table if we are starting to fill it up
        // Generally we prefer a sparse table
        //
        if( lsredis_preset_n >= lsredis_preset_max_n
        ) {
            lslogging_log_message( "lsredis_load_presets:
            increasing preset hash table size. max now %d", lsredis_preset_max_n
            );
            hdestroy_r( &lsredis_preset_ht);
            lsredis_preset_max_n *= 2;
            hcreate_r( 2 * lsredis_preset_max_n, &
            lsredis_preset_ht);
            for( pl = lsredis_preset_list; pl != NULL; pl = pl->
            next) {
                entry_in.key = pl->key;
                entry_in.data = pl;
                hsearch_r( entry_in, ENTER, &entry_outp, &lsredis_preset_ht
                );
            }
            lslogging_log_message( "lsredis_load_presets: done
            increasing preset hash table size.", lsredis_preset_max_n);
        }
    }
    free( preset_name);
}
pthread_mutex_unlock( &lsredis_preset_list_mutex);
}

```

7.12.4.66 int lsredis_regexec (const regex_t * preg, lsredis_obj_t * p, size_t nmatch, regmatch_t * pmatch, int eflags)

Definition at line 264 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);

    return rtn;
}

```

7.12.4.67 void lsredis_run ()

Definition at line 1219 of file lsredis.c.

```

    {
        pthread_create( &lsredis_thread, NULL, lsredis_worker
            , NULL);
    }

```

7.12.4.68 void lsredis_set_preset (char * base, char * preset_name, double dval)

set the given preset to the given value create a new preset if we can't find it

Definition at line 935 of file lsredis.c.

```

{
    char s[512];
    int plength;
    int err;
    ENTRY entry_in, *entry_outp;
    lsredis_obj_t *p, *presets_length_p;
    lsredis_preset_list_t *pl;

    snprintf( s, sizeof( s)-1, "%s%s", motor_name, preset_name);
    s[sizeof(s)-1] = 0;

    entry_in.key = s;
    entry_in.data = NULL;
    err = hsearch_r( entry_in, FIND, &entry_outp, &lsredis_preset_ht
        );
    if( err != 0) {
        //
        // Found it. Things are simple.
        //
        pl = entry_outp->data;
        lsredis_setstr( pl->position, "%.3f", dval);
        return;
    }
    //
    // OK, our preset was not found, add it
    //
    presets_length_p = lsredis_get_obj( "%s.presets.length",
        motor_name);
    plength = lsredis_get_or_set_l( presets_length_p, 0);
    plength += 1;

    snprintf( s, sizeof( s)-1, "%s.%s.presets.%d.name", lsredis_head,
        motor_name, plength-1);
    s[sizeof(s)-1] = 0;

    p = lsredis_get_obj( "%s.presets.%d.name", motor_name, plength
        -1);
    lsredis_setstr( p, "%s", preset_name);

    p = lsredis_get_obj( "%s.presets.%d.position", motor_name,
        plength-1);
    lsredis_setstr( p, "%.3f", dval);

    lsredis_setstr( presets_length_p, "%ld", plength);

    lsredis_load_presets( motor_name);
}

```

7.12.4.69 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. < up the count of times we need to see ourselves published before we start listening to others again

< Unlock to prevent deadlock in case the service routine needs to set our value

< `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 306 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);

    //
    // Don't send an update if a good value has not changed
    //
    if( p->valid && strcmp( v, p->value) == 0) {
        // nothing to do
        pthread_mutex_unlock( &p->mutex);
        return;
    }

    p->wait_for_me++;
    pthread_mutex_unlock( &p->mutex);

    argv[0] = "HSET";
    argv[1] = p->key;
    argv[2] = "VALUE";
    argv[3] = v;

    pthread_mutex_lock( &lsredis_mutex);
    while( lsredis_running == 0)
        pthread_cond_wait( &lsredis_cond, &lsredis_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_mutex);

    // Assume redis will take exactly the value we sent it
    //
    pthread_mutex_lock( &p->mutex);
    _lsredis_set_value( p, v);
    pthread_cond_signal( &p->cond);
    pthread_mutex_unlock( &p->mutex);
}

```

7.12.4.70 void `lstest_main` ()

Definition at line 92 of file `lstest.c`.

```

{
    lstest_lspmac_est_move_time();
}

```

7.12.4.71 void `lstimer_init` ()

Initialize the timer list and pthread stuff.

Definition at line 270 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);
    }

```

7.12.4.72 void `lstimer_run` ()

Start up our thread.

Definition at line 284 of file `lstimer.c`.

```

    {
        pthread_create( &lstimer_thread, NULL, lstimer_worker
            , NULL);
    }

```

7.12.4.73 void `lstimer_set_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 63 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);

        // Make sure our event is registered (saves a tiny bit of time later)
        //
        lsevents_preregister_event( event);

        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_set_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);
}

```

7.12.4.74 void lstimer_unset_timer (char * event)

Unsets all timers for the given event.

Definition at line 46 of file lstimer.c.

```

{
    int i;

    for( i=0; i<LSTIMER_LIST_LENGTH; i++) {
        if( strcmp( event, lstimer_list[i].event) == 0 ) {
            lstimer_list[i].shots = 0;
        }
    }
}

```

7.12.4.75 void lsupdate_init ()

7.12.4.76 void lsupdate_run ()

7.12.4.77 void md2cmds_init ()

Initialize the md2cmds module.

Definition at line 1853 of file md2cmds.c.

```

{
    ENTRY hloader, *hrtnval;
    int i, err;

    pthread_mutexattr_t mutex_initializer;

    pthread_mutexattr_init( &mutex_initializer);
    pthread_mutexattr_settype( &mutex_initializer, PTHREAD_MUTEX_RECURSIVE);

    pthread_mutex_init( &md2cmds_mutex, &mutex_initializer);
    pthread_cond_init( &md2cmds_cond, NULL);

    pthread_mutex_init( &md2cmds_moving_mutex, &
        mutex_initializer);
    pthread_cond_init( &md2cmds_moving_cond, NULL);

    pthread_mutex_init( &md2cmds_homing_mutex, &
        mutex_initializer);
    pthread_cond_init( &md2cmds_homing_cond, NULL);

    err = regcomp( &md2cmds_cmd_regex, " *([^\ ]+) (([^\ ]+)\|\\
        .presets\\.\\.)*([^\ ]*) *([^\ ]*)", REG_EXTENDED);
}

```

```

if( err != 0) {
    int nerrmsg;
    char *errmsg;

    nerrmsg = regerror( err, &md2cmds_cmd_regex, NULL, 0);
    if( nerrmsg > 0) {
        errmsg = calloc( nerrmsg, sizeof( char));
        nerrmsg = regerror( err, &md2cmds_cmd_regex, errmsg,
            nerrmsg);
        lslogging_log_message( "md2cmds_init: %s", errmsg);
        free( errmsg);
    }
}

md2cmds_md_status_code = lsredis_get_obj
    ( "md2_status_code");
lsredis_setstr( md2cmds_md_status_code, "
7");

hcreate_r( 2 * sizeof(md2cmds_cmd_kvs)/sizeof(md2cmds_cmd_kvs
    [0]), &md2cmds_hmap);
for( i=0; i<sizeof(md2cmds_cmd_kvs)/sizeof(md2cmds_cmd_kvs
    [0]); i++) {
    hloader.key = md2cmds_cmd_kvs[i].k;
    hloader.data = md2cmds_cmd_kvs[i].v;
    err = hsearch_r( hloader, ENTER, &hrtval, &md2cmds_hmap);
    if( err == 0) {
        lslogging_log_message( "md2cmds_init: hsearch_r
            returned an error for item %d: %s", i, strerror( errno));
    }
}
}
}

```

7.12.4.78 void md2cmds_run ()

Start up the thread.

Definition at line 1903 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( ".+ (Moving|In Position)",
        md2cmds_maybe_done_moving_cb);
    lsevents_add_listener( "(.+) (Homing|Homed)",
        md2cmds_maybe_done_homing_cb);
    lsevents_add_listener( "capz (Moving|In Position)",
        md2cmds_time_capz_cb);
    lsevents_add_listener( "Coordsys 1 Stopped",
        md2cmds_coordsys_1_stopped_cb);
    lsevents_add_listener( "Coordsys 2 Stopped",
        md2cmds_coordsys_2_stopped_cb);
    lsevents_add_listener( "Coordsys 3 Stopped",
        md2cmds_coordsys_3_stopped_cb);
    lsevents_add_listener( "Coordsys 4 Stopped",
        md2cmds_coordsys_4_stopped_cb);
    lsevents_add_listener( "Coordsys 5 Stopped",
        md2cmds_coordsys_5_stopped_cb);
    lsevents_add_listener( "Coordsys 7 Stopped",
        md2cmds_coordsys_7_stopped_cb);
    lsevents_add_listener( "cam.zoom Moving",
        md2cmds_set_scale_cb);
}

```

7.12.4.79 void pgpmac_printf (char *fmt, ...)

Terminal output routine ala printf.

Parameters

in	fmt	Printf style formatting string
----	-----	--------------------------------

Definition at line 330 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);  
    }
```

7.12.4.80 void PmacSockSendline (char * s)

7.12.5 Variable Documentation

7.12.5.1 lspmac_motor_t* alignx

Alignment stage X.

Definition at line 100 of file lspmac.c.

7.12.5.2 lspmac_motor_t* aligny

Alignment stage Y.

Definition at line 101 of file lspmac.c.

7.12.5.3 lspmac_motor_t* alignz

Alignment stage X.

Definition at line 102 of file lspmac.c.

7.12.5.4 lspmac_motor_t* anal

Polaroid analyzer motor.

Definition at line 103 of file lspmac.c.

7.12.5.5 lspmac_motor_t* apery

Aperture Y.

Definition at line 105 of file lspmac.c.

7.12.5.6 lspmac_motor_t* aperz

Aperture Z.

Definition at line 106 of file lspmac.c.

7.12.5.7 Ispmac_bi_t* arm_parked

(whose arm? parked where?)

Definition at line 143 of file Ispmac.c.

7.12.5.8 Ispmac_motor_t* blight

Back Light DAC.

Definition at line 117 of file Ispmac.c.

7.12.5.9 Ispmac_bi_t* blight_down

Backlight is down.

Definition at line 133 of file Ispmac.c.

7.12.5.10 Ispmac_motor_t* blight_f

Back light scale factor.

Definition at line 126 of file Ispmac.c.

7.12.5.11 Ispmac_motor_t* blight_ud

Back light Up/Down actuator.

Definition at line 121 of file Ispmac.c.

7.12.5.12 Ispmac_bi_t* blight_up

Backlight is up.

Definition at line 134 of file Ispmac.c.

7.12.5.13 Ispmac_motor_t* capy

Capillary Y.

Definition at line 107 of file Ispmac.c.

7.12.5.14 Ispmac_motor_t* capz

Capillary Z.

Definition at line 108 of file Ispmac.c.

7.12.5.15 Ispmac_motor_t* cenx

Centering Table X.

Definition at line 110 of file Ispmac.c.

7.12.5.16 Ispmac_motor_t* ceny

Centering Table Y.

Definition at line 111 of file Ispmac.c.

7.12.5.17 Ispmac_motor_t* cryo

Move the cryostream towards or away from the crystal.

Definition at line 122 of file Ispmac.c.

7.12.5.18 Ispmac_bi_t* cryo_back

cryo is in the back position

Definition at line 135 of file Ispmac.c.

7.12.5.19 Ispmac_bi_t* cryo_switch

that little toggle switch for the cryo

Definition at line 132 of file Ispmac.c.

7.12.5.20 Ispmac_motor_t* dryer

blow air on the scintillator to dry it off

Definition at line 123 of file Ispmac.c.

7.12.5.21 Ispmac_bi_t* etel_init_ok

ETEL initialized OK.

Definition at line 140 of file Ispmac.c.

7.12.5.22 Ispmac_bi_t* etel_on

ETEL is on.

Definition at line 139 of file Ispmac.c.

7.12.5.23 Ispmac_bi_t* etel_ready

ETEL is ready.

Definition at line 138 of file Ispmac.c.

7.12.5.24 Ispmac_motor_t* flight

Front Light DAC.

Definition at line 116 of file Ispmac.c.

7.12.5.25 lspmac_motor_t* flight_f

Front light scale factor.

Definition at line 127 of file lspmac.c.

7.12.5.26 lspmac_motor_t* flight_oo

Turn front light on/off.

Definition at line 125 of file lspmac.c.

7.12.5.27 lspmac_motor_t* fluo

Move the fluorescence detector in/out.

Definition at line 124 of file lspmac.c.

7.12.5.28 lspmac_bi_t* fluor_back

fluor is in the back position

Definition at line 136 of file lspmac.c.

7.12.5.29 lspmac_motor_t* fscint

Scintillator Piezo DAC.

Definition at line 118 of file lspmac.c.

7.12.5.30 lspmac_motor_t* fshut

Fast shutter.

Definition at line 115 of file lspmac.c.

7.12.5.31 lspmac_bi_t* hp_air

High pressure air OK.

Definition at line 131 of file lspmac.c.

7.12.5.32 lspmac_motor_t* kappa

Kappa.

Definition at line 112 of file lspmac.c.

7.12.5.33 lspmac_bi_t* lp_air

Low pressure air OK.

Definition at line 130 of file lspmac.c.

7.12.5.34 lspg_demandairrights_t lspg_demandairrights

our demandairrights object

Definition at line 65 of file lspg.c.

7.12.5.35 lspg_getcenter_t lspg_getcenter

the getcenter object

Definition at line 64 of file lspg.c.

7.12.5.36 lspg_getcurrentsampleid_t lspg_getcurrentsampleid

our currentsample id

Definition at line 66 of file lspg.c.

7.12.5.37 lspg_nextsample_t lspg_nextsample

the very next sample

Definition at line 62 of file lspg.c.

7.12.5.38 lspg_nextshot_t lspg_nextshot

the nextshot object

Definition at line 63 of file lspg.c.

7.12.5.39 lspg_starttransfer_t lspg_starttransfer

start a sample transfer

Definition at line 67 of file lspg.c.

7.12.5.40 lspg_waitcryo_t lspg_waitcryo

signal the robot

Definition at line 68 of file lspg.c.

7.12.5.41 lspmac_motor_t lspmac_motors[]

All our motors.

Definition at line 95 of file lspmac.c.

7.12.5.42 pthread_cond_t lspmac_moving_cond

Wait for motor(s) to finish moving condition.

Definition at line 71 of file lspmac.c.

7.12.5.43 `int lspmac_moving_flags`

Flag used to implement motor moving condition.

Definition at line 72 of file `lspmac.c`.

7.12.5.44 `pthread_mutex_t lspmac_moving_mutex`

Coordinate moving motors between threads.

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

7.12.5.45 `int lspmac_nmotors`

The number of motors we manage.

Definition at line 96 of file `lspmac.c`.

7.12.5.46 `pthread_cond_t lspmac_shutter_cond`

Allows waiting for the shutter status to change.

Definition at line 69 of file `lspmac.c`.

7.12.5.47 `int lspmac_shutter_has_opened`

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

Definition at line 67 of file `lspmac.c`.

7.12.5.48 `pthread_mutex_t lspmac_shutter_mutex`

Coordinates threads reading shutter status.

Definition at line 68 of file `lspmac.c`.

7.12.5.49 `int lspmac_shutter_state`

State of the shutter, used to detect changes.

Definition at line 66 of file `lspmac.c`.

7.12.5.50 `pthread_cond_t lsredis_cond`

Definition at line 75 of file `lsredis.c`.

7.12.5.51 `pthread_mutex_t lsredis_mutex`

Definition at line 74 of file `lsredis.c`.

7.12.5.52 `int lsredis_running`

Definition at line 76 of file `lsredis.c`.

7.12.5.53 pthread_mutex_t md2_status_mutex

Synchronize reading/writing status buffer.

Definition at line 351 of file lspmac.c.

7.12.5.54 char md2cmds_cmd[]

our command;

Definition at line 24 of file md2cmds.c.

7.12.5.55 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.

7.12.5.56 lsredis_obj_t* md2cmds_md_status_code

Definition at line 26 of file md2cmds.c.

7.12.5.57 pthread_mutex_t md2cmds_mutex

mutex for the condition

Definition at line 11 of file md2cmds.c.

7.12.5.58 pthread_cond_t md2cmds_pg_cond**7.12.5.59 pthread_mutex_t md2cmds_pg_mutex****7.12.5.60 lspmac_bi_t* minikappa_ok**

Minikappa is OK (whatever that means)

Definition at line 141 of file lspmac.c.

7.12.5.61 pthread_mutex_t ncurses_mutex

allow more than one thread access to the screen

Definition at line 242 of file pgpmac.c.

7.12.5.62 lspmac_motor_t* omega

MD2 omega axis (the air bearing)

Definition at line 99 of file lspmac.c.

7.12.5.63 struct timespec omega_zero_time

Time we believe that omega crossed zero.

Definition at line 79 of file lspmac.c.

7.12.5.64 `lspmac_motor_t* phi`

Phi (not data collection axis)

Definition at line 113 of file `lspmac.c`.

7.12.5.65 `pthread_cond_t pmac_queue_cond`

wait for a command to be sent to PMAC before continuing

Definition at line 85 of file `lspmac.c`.

7.12.5.66 `pthread_mutex_t pmac_queue_mutex`

manage access to the pmac command queue

Definition at line 84 of file `lspmac.c`.

7.12.5.67 `lspmac_bi_t* sample_detected`

smart magnet detected sample

Definition at line 137 of file `lspmac.c`.

7.12.5.68 `lspmac_motor_t* scint`

Scintillator Z.

Definition at line 109 of file `lspmac.c`.

7.12.5.69 `lspmac_bi_t* shutter_open`

shutter is open (note in pmc says this is a slow input)

Definition at line 144 of file `lspmac.c`.

7.12.5.70 `lspmac_bi_t* smart_mag_err`

smart magnet error (coil broken perhaps)

Definition at line 145 of file `lspmac.c`.

7.12.5.71 `lspmac_bi_t* smart_mag_off`

smart magnet is off

Definition at line 146 of file `lspmac.c`.

7.12.5.72 `lspmac_bi_t* smart_mag_on`

smart magnet is on

Definition at line 142 of file `lspmac.c`.

7.12.5.73 lspmac_motor_t* smart_mag_oo

Smart Magnet on/off.

Definition at line 120 of file lspmac.c.

7.12.5.74 WINDOW* term_input

place to put the cursor

Definition at line 238 of file pgpmac.c.

7.12.5.75 WINDOW* term_output

place to print stuff out

Definition at line 237 of file pgpmac.c.

7.12.5.76 WINDOW* term_status

shutter, lamp, air, etc status

Definition at line 239 of file pgpmac.c.

7.12.5.77 WINDOW* term_status2

shutter, lamp, air, etc status

Definition at line 240 of file pgpmac.c.

7.12.5.78 lspmac_motor_t* zoom

Optical zoom.

Definition at line 104 of file lspmac.c.

Index

- [_GNU_SOURCE](#)
 - [pgpmac.h, 294](#)
- [__init__](#)
 - [iniParser::iniParser, 16](#)
- [_lspmac_motor_init](#)
 - [lspmac.c, 143](#)
- [_lsredis_get_obj](#)
 - [lsredis.c, 219](#)
 - [pgpmac.h, 296](#)
- [_lsredis_set_value](#)
 - [lsredis.c, 220](#)
- [acc11c_1](#)
 - [md2StatusStruct, 64](#)
- [acc11c_2](#)
 - [md2StatusStruct, 64](#)
- [acc11c_3](#)
 - [md2StatusStruct, 64](#)
- [acc11c_5](#)
 - [md2StatusStruct, 64](#)
- [acc11c_6](#)
 - [md2StatusStruct, 64](#)
- [active](#)
 - [lspg_nextshot_struct, 31](#)
 - [lspmac_motor_struct, 50](#)
- [active2](#)
 - [lspg_nextshot_struct, 31](#)
- [active2_isnull](#)
 - [lspg_nextshot_struct, 31](#)
- [active_init](#)
 - [lspmac_motor_struct, 50](#)
- [active_isnull](#)
 - [lspg_nextshot_struct, 31](#)
- [active_simulation](#)
 - [mk_pgpmac_redis, 12](#)
- [actual_pos_cnts](#)
 - [lspmac_motor_struct, 50](#)
- [actual_pos_cnts_p](#)
 - [lspmac_motor_struct, 51](#)
- [alignx](#)
 - [lspmac.c, 206](#)
 - [pgpmac.h, 341](#)
- [alignx_act_pos](#)
 - [md2StatusStruct, 64](#)
- [alignx_status_1](#)
 - [md2StatusStruct, 64](#)
- [alignx_status_2](#)
 - [md2StatusStruct, 64](#)
- [aligny](#)
 - [lspmac.c, 206](#)
- [pgpmac.h, 341](#)
- [aligny_act_pos](#)
 - [md2StatusStruct, 64](#)
- [aligny_status_1](#)
 - [md2StatusStruct, 64](#)
- [aligny_status_2](#)
 - [md2StatusStruct, 65](#)
- [alignz](#)
 - [lspmac.c, 206](#)
 - [pgpmac.h, 341](#)
- [alignz_act_pos](#)
 - [md2StatusStruct, 65](#)
- [alignz_status_1](#)
 - [md2StatusStruct, 65](#)
- [alignz_status_2](#)
 - [md2StatusStruct, 65](#)
- [anal](#)
 - [lspmac.c, 206](#)
 - [pgpmac.h, 341](#)
- [analyzer_act_pos](#)
 - [md2StatusStruct, 65](#)
- [analyzer_status_1](#)
 - [md2StatusStruct, 65](#)
- [analyzer_status_2](#)
 - [md2StatusStruct, 65](#)
- [aperturey_act_pos](#)
 - [md2StatusStruct, 65](#)
- [aperturey_status_1](#)
 - [md2StatusStruct, 65](#)
- [aperturey_status_2](#)
 - [md2StatusStruct, 65](#)
- [aperturez_act_pos](#)
 - [md2StatusStruct, 65](#)
- [aperturez_status_1](#)
 - [md2StatusStruct, 65](#)
- [aperturez_status_2](#)
 - [md2StatusStruct, 66](#)
- [apery](#)
 - [lspmac.c, 207](#)
 - [pgpmac.h, 341](#)
- [aperz](#)
 - [lspmac.c, 207](#)
 - [pgpmac.h, 341](#)
- [arm_parked](#)
 - [lspmac.c, 207](#)
 - [pgpmac.h, 341](#)
- [asis](#)
 - [mk_pgpmac_redis, 12](#)
- [avalue](#)

- lsredis_obj_struct, [57](#)
- ax
 - lspg_nextshot_struct, [31](#)
- ax2
 - lspg_nextshot_struct, [31](#)
- ax2_isnull
 - lspg_nextshot_struct, [31](#)
- ax_isnull
 - lspg_nextshot_struct, [31](#)
- axis
 - lspmac_combined_move_struct, [47](#)
 - lspmac_motor_struct, [51](#)
- ay
 - lspg_nextshot_struct, [31](#)
- ay2
 - lspg_nextshot_struct, [32](#)
- ay2_isnull
 - lspg_nextshot_struct, [32](#)
- ay_isnull
 - lspg_nextshot_struct, [32](#)
- az
 - lspg_nextshot_struct, [32](#)
- az2
 - lspg_nextshot_struct, [32](#)
- az2_isnull
 - lspg_nextshot_struct, [32](#)
- az_isnull
 - lspg_nextshot_struct, [32](#)
- b
 - mk_pgpmac_redis, [12](#)
- bData
 - tagEthernetCmd, [70](#)
- back_dac
 - md2StatusStruct, [66](#)
- bi_list
 - mk_pgpmac_redis, [12](#)
- blight
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- blight_down
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- blight_f
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- blight_ud
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- blight_up
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- bvalue
 - lsredis_obj_struct, [57](#)
- capy
 - lspmac.c, [207](#)
 - pgpmac.h, [342](#)
- capy_act_pos
 - md2StatusStruct, [66](#)
- capy_status_1
 - md2StatusStruct, [66](#)
- capy_status_2
 - md2StatusStruct, [66](#)
- capz
 - lspmac.c, [208](#)
 - pgpmac.h, [342](#)
- capz_act_pos
 - md2StatusStruct, [66](#)
- capz_status_1
 - md2StatusStruct, [66](#)
- capz_status_2
 - md2StatusStruct, [66](#)
- cb
 - lsevents_callbacks_struct, [18](#)
 - lsevents_listener_struct, [19](#)
- cbl
 - lsevents_event_names_struct, [18](#)
- centerx_act_pos
 - md2StatusStruct, [66](#)
- centerx_status_1
 - md2StatusStruct, [66](#)
- centerx_status_2
 - md2StatusStruct, [66](#)
- centery_act_pos
 - md2StatusStruct, [66](#)
- centery_status_1
 - md2StatusStruct, [67](#)
- centery_status_2
 - md2StatusStruct, [67](#)
- cenx
 - lspmac.c, [208](#)
 - pgpmac.h, [342](#)
- ceny
 - lspmac.c, [208](#)
 - pgpmac.h, [342](#)
- changeEventOff
 - lspmac_bi_struct, [45](#)
- changeEventOn
 - lspmac_bi_struct, [45](#)
- cleanstr
 - lspmac.c, [144](#)
- command_buf
 - lspmac_ascii_buffers_struct, [43](#)
- command_buf_cc
 - lspmac_ascii_buffers_struct, [43](#)
- command_sent
 - lspmac_motor_struct, [51](#)
- command_str
 - lspmac_ascii_buffers_struct, [43](#)
- cond
 - lspg_demandairrights_struct, [21](#)
 - lspg_getcenter_struct, [22](#)
 - lspg_getcurrentsampleid_struct, [25](#)
 - lspg_lock_detector_struct, [26](#)
 - lspg_lock_diffractionmeter_struct, [26](#)
 - lspg_nextsample_struct, [27](#)

- lspg_nextshot_struct, 32
- lspg_seq_run_prep_struct, 39
- lspg_starttransfer_struct, 40
- lspg_wait_for_detector_struct, 41
- lspg_waitcryo_struct, 42
- lspmac_motor_struct, 51
- lsredis_obj_struct, 57
- coord_num
 - lspmac_combined_move_struct, 47
 - lspmac_motor_struct, 51
- cr_cmd
 - lspmac.c, 208
- cryo
 - lspmac.c, 208
 - pgpmac.h, 343
- cryo_back
 - lspmac.c, 208
 - pgpmac.h, 343
- cryo_switch
 - lspmac.c, 208
 - pgpmac.h, 343
- cvalue
 - lsredis_obj_struct, 57
- cx
 - lspg_nextshot_struct, 32
- cx2
 - lspg_nextshot_struct, 32
- cx2_isnull
 - lspg_nextshot_struct, 33
- cx_isnull
 - lspg_nextshot_struct, 33
- cy
 - lspg_nextshot_struct, 33
- cy2
 - lspg_nextshot_struct, 33
- cy2_isnull
 - lspg_nextshot_struct, 33
- cy_isnull
 - lspg_nextshot_struct, 33
- dac_mvar
 - lspmac_motor_struct, 51
- dax
 - lspg_getcenter_struct, 22
- dax_isnull
 - lspg_getcenter_struct, 23
- day
 - lspg_getcenter_struct, 23
- day_isnull
 - lspg_getcenter_struct, 23
- daz
 - lspg_getcenter_struct, 23
- daz_isnull
 - lspg_getcenter_struct, 23
- dbmem
 - lspmac.c, 208
- dbmemIn
 - lspmac.c, 208
- dcx
 - lspg_getcenter_struct, 23
- dcx_isnull
 - lspg_getcenter_struct, 23
- dcy
 - lspg_getcenter_struct, 23
- dcy_isnull
 - lspg_getcenter_struct, 23
- delay_nsecs
 - lstimer_list_struct, 60
- delay_secs
 - lstimer_list_struct, 60
- Delta
 - lspmac_combined_move_struct, 47
- dryer
 - lspmac.c, 209
 - pgpmac.h, 343
- dsdir
 - lspg_nextshot_struct, 33
- dsdir_isnull
 - lspg_nextshot_struct, 33
- dsdist
 - lspg_nextshot_struct, 33
- dsdist2
 - lspg_nextshot_struct, 33
- dsdist2_isnull
 - lspg_nextshot_struct, 34
- dsdist_isnull
 - lspg_nextshot_struct, 34
- dsexp
 - lspg_nextshot_struct, 34
- dsexp2
 - lspg_nextshot_struct, 34
- dsexp2_isnull
 - lspg_nextshot_struct, 34
- dsexp_isnull
 - lspg_nextshot_struct, 34
- dshpid
 - lspg_nextshot_struct, 34
- dshpid_isnull
 - lspg_nextshot_struct, 34
- dskappa
 - lspg_nextshot_struct, 34
- dskappa2
 - lspg_nextshot_struct, 34
- dskappa2_isnull
 - lspg_nextshot_struct, 35
- dskappa_isnull
 - lspg_nextshot_struct, 35
- dsnrg
 - lspg_nextshot_struct, 35
- dsnrg2
 - lspg_nextshot_struct, 35
- dsnrg2_isnull
 - lspg_nextshot_struct, 35
- dsnrg_isnull
 - lspg_nextshot_struct, 35
- dsomega
 - lspg_nextshot_struct, 35

- dsomega2
 - lspg_nextshot_struct, [35](#)
- dsomega2_isnull
 - lspg_nextshot_struct, [35](#)
- dsomega_isnull
 - lspg_nextshot_struct, [35](#)
- dsoscaxis
 - lspg_nextshot_struct, [35](#)
- dsoscaxis2
 - lspg_nextshot_struct, [36](#)
- dsoscaxis2_isnull
 - lspg_nextshot_struct, [36](#)
- dsoscaxis_isnull
 - lspg_nextshot_struct, [36](#)
- dsowidth
 - lspg_nextshot_struct, [36](#)
- dsowidth2
 - lspg_nextshot_struct, [36](#)
- dsowidth2_isnull
 - lspg_nextshot_struct, [36](#)
- dsowidth_isnull
 - lspg_nextshot_struct, [36](#)
- dsphi
 - lspg_nextshot_struct, [36](#)
- dsphi2
 - lspg_nextshot_struct, [36](#)
- dsphi2_isnull
 - lspg_nextshot_struct, [36](#)
- dsphi_isnull
 - lspg_nextshot_struct, [37](#)
- dspid
 - lspg_nextshot_struct, [37](#)
- dspid_isnull
 - lspg_nextshot_struct, [37](#)
- dummy1
 - md2StatusStruct, [67](#)
- dummy2
 - md2StatusStruct, [67](#)
- dummy3
 - md2StatusStruct, [67](#)
- dummy4
 - md2StatusStruct, [67](#)
- dummy5
 - md2StatusStruct, [67](#)
- dummy6
 - md2StatusStruct, [67](#)
- dummy7
 - md2StatusStruct, [67](#)
- dummy8
 - md2StatusStruct, [67](#)
- dummy9
 - md2StatusStruct, [67](#)
- dummyA
 - md2StatusStruct, [67](#)
- dummyB
 - md2StatusStruct, [68](#)
- dvalue
 - lsredis_obj_struct, [57](#)
- etel_init_ok
 - lspmac.c, [209](#)
 - pgpmac.h, [343](#)
- etel_on
 - lspmac.c, [209](#)
 - pgpmac.h, [343](#)
- etel_ready
 - lspmac.c, [209](#)
 - pgpmac.h, [343](#)
- ethCmdOff
 - lspmac.c, [209](#)
- ethCmdOn
 - lspmac.c, [209](#)
- ethCmdQueue
 - lspmac.c, [209](#)
- ethCmdReply
 - lspmac.c, [209](#)
- event
 - lsevents_event_names_struct, [18](#)
 - lspmac_cmd_queue_struct, [46](#)
 - lspmac_dpascii_queue_struct, [48](#)
 - lstimer_list_struct, [61](#)
- events_name
 - lsredis_obj_struct, [58](#)
- evp
 - lsevents_queue_struct, [20](#)
- f
 - iniParser::iniParser, [17](#)
 - mk_pgpmac_redis, [12](#)
- first_time
 - lspmac_bi_struct, [45](#)
- flight
 - lspmac.c, [209](#)
 - pgpmac.h, [343](#)
- flight_f
 - lspmac.c, [210](#)
 - pgpmac.h, [343](#)
- flight_oo
 - lspmac.c, [210](#)
 - pgpmac.h, [344](#)
- fluo
 - lspmac.c, [210](#)
 - pgpmac.h, [344](#)
- fluor_back
 - lspmac.c, [210](#)
 - pgpmac.h, [344](#)
- fnc
 - mk_pgpmac_redis, [12](#)
- front_dac
 - md2StatusStruct, [68](#)
- fs_has_opened
 - md2StatusStruct, [68](#)
- fs_has_opened_globally
 - md2StatusStruct, [68](#)
- fs_is_open
 - md2StatusStruct, [68](#)
- fscint
 - lspmac.c, [210](#)

- pgpmac.h, 344
- fshut
 - lspmac.c, 210
 - pgpmac.h, 344
- gb_cmd
 - lspmac.c, 210
- get
 - iniParser::iniParser, 16
- getcurrentsampleid
 - lspg_getcurrentsampleid_struct, 25
- getcurrentsampleid_isnull
 - lspg_getcurrentsampleid_struct, 25
- getivars
 - lspmac.c, 210
- getmvars
 - lspmac.c, 210
- handler
 - lstimer.c, 242
- hard_ini
 - mk_pgpmac_redis, 12
- hard_ini_fields
 - mk_pgpmac_redis, 13
- has_option
 - iniParser::iniParser, 16
- has_section
 - iniParser::iniParser, 16
- head
 - mk_pgpmac_redis, 13
- hex_dump
 - lspmac.c, 144
- hi
 - mk_pgpmac_redis, 13
- hits
 - lsredis_obj_struct, 58
- home
 - lspmac_motor_struct, 51
- homing
 - lspmac_motor_struct, 51
- hp_air
 - lspmac.c, 211
 - pgpmac.h, 344
- i
 - mk_pgpmac_redis, 13
- in_position_band
 - lspmac_motor_struct, 51
- inactive_init
 - lspmac_motor_struct, 52
- index
 - lsredis_preset_list_struct, 59
- iniParser, 11
 - ip, 11
- iniParser.iniParser, 15
- iniParser.py, 73
- iniParser::iniParser
 - __init__, 16
 - f, 17
 - get, 16
 - has_option, 16
 - has_section, 16
 - options, 16
 - read, 16
 - sd, 17
 - sections, 17
- init_nsecs
 - lstimer_list_struct, 61
- init_secs
 - lstimer_list_struct, 61
- ip
 - iniParser, 11
- jogAbs
 - lspmac_motor_struct, 52
- k
 - md2cmds_cmd_kv_struct, 62
- kappa
 - lspmac.c, 211
 - pgpmac.h, 344
- kappa_act_pos
 - md2StatusStruct, 68
- kappa_status_1
 - md2StatusStruct, 68
- kappa_status_2
 - md2StatusStruct, 68
- key
 - lsredis_obj_struct, 58
 - lsredis_preset_list_struct, 59
- LS_PG_STATE_IDLE
 - lspg.c, 92
- LS_PG_STATE_INIT
 - lspg.c, 92
- LS_PG_STATE_RECV
 - lspg.c, 92
- LS_PG_STATE_RESET
 - lspg.c, 92
- LS_PG_STATE_SEND
 - lspg.c, 93
- LS_PMAC_STATE_CR
 - lspmac.c, 139
- LS_PMAC_STATE_GB
 - lspmac.c, 139
- LS_PMAC_STATE_GMR
 - lspmac.c, 139
- LS_PMAC_STATE_IDLE
 - lspmac.c, 139
- LS_PMAC_STATE_RESET
 - lspmac.c, 139
- LS_PMAC_STATE_RR
 - lspmac.c, 140
- LS_PMAC_STATE_SC
 - lspmac.c, 140
- LS_PMAC_STATE_WACK
 - lspmac.c, 140
- LS_PMAC_STATE_WCR

- lspmac.c, [140](#)
- LS_PMAC_STATE_WGB
 - lspmac.c, [140](#)
- LSLOGGING_FILE_NAME
 - lslogging.c, [83](#)
- LSPMAC_MAGIC_NUMBER
 - pgpmac.h, [294](#)
- LSPMAC_MAX_MOTORS
 - lspmac.c, [140](#)
- LSPMAC_PRESET_REGEX
 - lspmac.c, [140](#)
- LSTIMER_LIST_LENGTH
 - lstimer.c, [241](#)
- last_nsecs
 - lstimer_list_struct, [61](#)
- last_secs
 - lstimer_list_struct, [61](#)
- lmsg
 - lslogging_queue_struct, [21](#)
- lp_air
 - lspmac.c, [211](#)
 - pgpmac.h, [344](#)
- ls_pg_state
 - lspg.c, [127](#)
- ls_pmac_state
 - lspmac.c, [211](#)
- lsConnect
 - lspmac.c, [145](#)
- lsevents.c, [73](#)
 - lsevents_add_listener, [76](#)
 - lsevents_callbacks_t, [75](#)
 - lsevents_event_name_ht, [81](#)
 - lsevents_event_names, [81](#)
 - lsevents_event_names_t, [75](#)
 - lsevents_init, [76](#)
 - lsevents_listener_mutex, [81](#)
 - lsevents_listener_t, [75](#)
 - lsevents_listeners_p, [81](#)
 - lsevents_max_events, [81](#)
 - lsevents_n_events, [81](#)
 - lsevents_preregister_event, [77](#)
 - lsevents_queue, [81](#)
 - lsevents_queue_cond, [81](#)
 - lsevents_queue_mutex, [81](#)
 - lsevents_queue_off, [81](#)
 - lsevents_queue_on, [82](#)
 - lsevents_queue_t, [75](#)
 - lsevents_register_event, [77](#)
 - lsevents_remove_listener, [78](#)
 - lsevents_run, [79](#)
 - lsevents_send_event, [79](#)
 - lsevents_thread, [82](#)
 - lsevents_worker, [80](#)
- lsevents_add_listener
 - lsevents.c, [76](#)
 - pgpmac.h, [297](#)
- lsevents_callbacks_struct, [17](#)
 - cb, [18](#)
- next, [18](#)
- lsevents_callbacks_t
 - lsevents.c, [75](#)
- lsevents_event_name_ht
 - lsevents.c, [81](#)
- lsevents_event_names
 - lsevents.c, [81](#)
- lsevents_event_names_struct, [18](#)
 - cbl, [18](#)
 - event, [18](#)
 - next, [18](#)
- lsevents_event_names_t
 - lsevents.c, [75](#)
- lsevents_init
 - lsevents.c, [76](#)
 - pgpmac.h, [298](#)
- lsevents_listener_mutex
 - lsevents.c, [81](#)
- lsevents_listener_struct, [19](#)
 - cb, [19](#)
 - next, [19](#)
 - raw_regexp, [19](#)
 - re, [19](#)
- lsevents_listener_t
 - lsevents.c, [75](#)
- lsevents_listeners_p
 - lsevents.c, [81](#)
- lsevents_max_events
 - lsevents.c, [81](#)
- lsevents_n_events
 - lsevents.c, [81](#)
- lsevents_preregister_event
 - lsevents.c, [77](#)
 - pgpmac.h, [298](#)
- lsevents_queue
 - lsevents.c, [81](#)
- lsevents_queue_cond
 - lsevents.c, [81](#)
- lsevents_queue_mutex
 - lsevents.c, [81](#)
- lsevents_queue_off
 - lsevents.c, [81](#)
- lsevents_queue_on
 - lsevents.c, [82](#)
- lsevents_queue_struct, [20](#)
 - evp, [20](#)
- lsevents_queue_t
 - lsevents.c, [75](#)
- lsevents_register_event
 - lsevents.c, [77](#)
- lsevents_remove_listener
 - lsevents.c, [78](#)
 - pgpmac.h, [298](#)
- lsevents_run
 - lsevents.c, [79](#)
 - pgpmac.h, [299](#)
- lsevents_send_event
 - lsevents.c, [79](#)

- pgpmac.h, 300
- lsevents_thread
 - lsevents.c, 82
- lsevents_worker
 - lsevents.c, 80
- lslogging.c, 82
 - LSLOGGING_FILE_NAME, 83
 - lslogging_cond, 86
 - lslogging_event_cb, 84
 - lslogging_file, 86
 - lslogging_init, 84
 - lslogging_log_message, 84
 - lslogging_mutex, 86
 - lslogging_off, 86
 - lslogging_on, 86
 - lslogging_queue, 86
 - lslogging_queue_t, 84
 - lslogging_run, 85
 - lslogging_thread, 86
 - lslogging_worker, 85
- lslogging_cond
 - lslogging.c, 86
- lslogging_event_cb
 - lslogging.c, 84
- lslogging_file
 - lslogging.c, 86
- lslogging_init
 - lslogging.c, 84
 - pgpmac.h, 300
- lslogging_log_message
 - lslogging.c, 84
 - pgpmac.h, 300
- lslogging_mutex
 - lslogging.c, 86
- lslogging_off
 - lslogging.c, 86
- lslogging_on
 - lslogging.c, 86
- lslogging_queue
 - lslogging.c, 86
- lslogging_queue_struct, 20
 - lmsg, 21
 - ltime, 21
- lslogging_queue_t
 - lslogging.c, 84
- lslogging_run
 - lslogging.c, 85
 - pgpmac.h, 301
- lslogging_thread
 - lslogging.c, 86
- lslogging_worker
 - lslogging.c, 85
- lspg.c, 86
 - LS_PG_STATE_IDLE, 92
 - LS_PG_STATE_INIT, 92
 - LS_PG_STATE_RECV, 92
 - LS_PG_STATE_RESET, 92
 - LS_PG_STATE_SEND, 93
 - ls_pg_state, 127
 - lspg_allkvs_cb, 93
 - lspg_array2ptrs, 94
 - lspg_check_preset_in_position_cb, 95
 - lspg_cmd_cb, 96
 - lspg_connectPoll_response, 127
 - lspg_demandairrights, 127
 - lspg_demandairrights_all, 96
 - lspg_demandairrights_call, 96
 - lspg_demandairrights_cb, 97
 - lspg_demandairrights_init, 97
 - lspg_demandairrights_wait, 97
 - lspg_flush, 97
 - lspg_getcenter, 127
 - lspg_getcenter_all, 98
 - lspg_getcenter_call, 98
 - lspg_getcenter_cb, 98
 - lspg_getcenter_done, 99
 - lspg_getcenter_init, 99
 - lspg_getcenter_wait, 99
 - lspg_getcurrentsampleid, 127
 - lspg_getcurrentsampleid_call, 100
 - lspg_getcurrentsampleid_cb, 100
 - lspg_getcurrentsampleid_init, 100
 - lspg_getcurrentsampleid_read, 100
 - lspg_getcurrentsampleid_wait_for_id, 101
 - lspg_init, 101
 - lspg_lock_detector, 127
 - lspg_lock_detector_all, 101
 - lspg_lock_detector_call, 102
 - lspg_lock_detector_cb, 102
 - lspg_lock_detector_done, 102
 - lspg_lock_detector_init, 102
 - lspg_lock_detector_t, 93
 - lspg_lock_detector_wait, 102
 - lspg_lock_diffractionmeter, 128
 - lspg_lock_diffractionmeter_all, 103
 - lspg_lock_diffractionmeter_call, 103
 - lspg_lock_diffractionmeter_cb, 103
 - lspg_lock_diffractionmeter_done, 103
 - lspg_lock_diffractionmeter_init, 104
 - lspg_lock_diffractionmeter_t, 93
 - lspg_lock_diffractionmeter_wait, 104
 - lspg_next_state, 104
 - lspg_nextaction_cb, 105
 - lspg_nextsample, 128
 - lspg_nextsample_all, 105
 - lspg_nextsample_call, 106
 - lspg_nextsample_cb, 106
 - lspg_nextsample_done, 107
 - lspg_nextsample_init, 107
 - lspg_nextsample_wait, 107
 - lspg_nextshot, 128
 - lspg_nextshot_call, 107
 - lspg_nextshot_cb, 107
 - lspg_nextshot_done, 111
 - lspg_nextshot_init, 111
 - lspg_nextshot_wait, 112

- lspg_notice_processor, 112
- lspg_pg_connect, 112
- lspg_pg_service, 113
- lspg_preset_changed_cb, 115
- lspg_query_next, 115
- lspg_query_push, 115
- lspg_query_queue, 128
- lspg_query_queue_off, 128
- lspg_query_queue_on, 128
- lspg_query_queue_reply, 128
- lspg_query_reply_next, 116
- lspg_query_reply_peek, 116
- lspg_queue_cond, 128
- lspg_queue_mutex, 128
- lspg_receive, 117
- lspg_resetPoll_response, 129
- lspg_run, 117
- lspg_sample_detector_cb, 118
- lspg_send_next_query, 118
- lspg_seq_run_prep, 129
- lspg_seq_run_prep_all, 119
- lspg_seq_run_prep_call, 119
- lspg_seq_run_prep_cb, 120
- lspg_seq_run_prep_done, 120
- lspg_seq_run_prep_init, 120
- lspg_seq_run_prep_t, 93
- lspg_seq_run_prep_wait, 120
- lspg_set_scale_cb, 120
- lspg_sig_service, 121
- lspg_starttransfer, 129
- lspg_starttransfer_all, 121
- lspg_starttransfer_call, 122
- lspg_starttransfer_cb, 122
- lspg_starttransfer_done, 122
- lspg_starttransfer_init, 122
- lspg_starttransfer_wait, 123
- lspg_thread, 129
- lspg_unset_current_preset_moving_cb, 123
- lspg_update_kvs_cb, 123
- lspg_wait_for_detector, 129
- lspg_wait_for_detector_all, 124
- lspg_wait_for_detector_call, 124
- lspg_wait_for_detector_cb, 124
- lspg_wait_for_detector_done, 125
- lspg_wait_for_detector_init, 125
- lspg_wait_for_detector_t, 93
- lspg_wait_for_detector_wait, 125
- lspg_waitcryo, 129
- lspg_waitcryo_all, 125
- lspg_waitcryo_cb, 126
- lspg_waitcryo_init, 126
- lspg_worker, 126
- lspgfd, 129
- now, 129
- q, 129
- lspg_allkvs_cb
 - lspg.c, 93
- lspg_array2ptrs
 - lspg.c, 94
 - pgpmac.h, 301
- lspg_check_preset_in_position_cb
 - lspg.c, 95
- lspg_cmd_cb
 - lspg.c, 96
- lspg_connectPoll_response
 - lspg.c, 127
- lspg_demandairrights
 - lspg.c, 127
 - pgpmac.h, 344
- lspg_demandairrights_all
 - lspg.c, 96
 - pgpmac.h, 303
- lspg_demandairrights_call
 - lspg.c, 96
- lspg_demandairrights_cb
 - lspg.c, 97
- lspg_demandairrights_init
 - lspg.c, 97
- lspg_demandairrights_struct, 21
 - cond, 21
 - mutex, 21
 - new_value_ready, 21
- lspg_demandairrights_t
 - pgpmac.h, 295
- lspg_demandairrights_wait
 - lspg.c, 97
- lspg_flush
 - lspg.c, 97
- lspg_getcenter
 - lspg.c, 127
 - pgpmac.h, 345
- lspg_getcenter_all
 - lspg.c, 98
- lspg_getcenter_call
 - lspg.c, 98
 - pgpmac.h, 303
- lspg_getcenter_cb
 - lspg.c, 98
- lspg_getcenter_done
 - lspg.c, 99
 - pgpmac.h, 303
- lspg_getcenter_init
 - lspg.c, 99
- lspg_getcenter_struct, 22
 - cond, 22
 - dax, 22
 - dax_isnull, 23
 - day, 23
 - day_isnull, 23
 - daz, 23
 - daz_isnull, 23
 - dcx, 23
 - dcx_isnull, 23
 - dcy, 23
 - dcy_isnull, 23
 - mutex, 23

- new_value_ready, [24](#)
- no_rows_returned, [24](#)
- zoom, [24](#)
- zoom_isnull, [24](#)
- lspg_getcenter_t
 - pgpmac.h, [295](#)
- lspg_getcenter_wait
 - lspg.c, [99](#)
 - pgpmac.h, [303](#)
- lspg_getcurrentsampleid
 - lspg.c, [127](#)
 - pgpmac.h, [345](#)
- lspg_getcurrentsampleid_call
 - lspg.c, [100](#)
- lspg_getcurrentsampleid_cb
 - lspg.c, [100](#)
- lspg_getcurrentsampleid_init
 - lspg.c, [100](#)
- lspg_getcurrentsampleid_read
 - lspg.c, [100](#)
- lspg_getcurrentsampleid_struct, [24](#)
 - cond, [25](#)
 - getcurrentsampleid, [25](#)
 - getcurrentsampleid_isnull, [25](#)
 - mutex, [25](#)
 - new_value_ready, [25](#)
 - no_rows_returned, [25](#)
- lspg_getcurrentsampleid_t
 - pgpmac.h, [295](#)
- lspg_getcurrentsampleid_wait_for_id
 - lspg.c, [101](#)
 - pgpmac.h, [303](#)
- lspg_init
 - lspg.c, [101](#)
 - pgpmac.h, [304](#)
- lspg_lock_detector
 - lspg.c, [127](#)
- lspg_lock_detector_all
 - lspg.c, [101](#)
- lspg_lock_detector_call
 - lspg.c, [102](#)
- lspg_lock_detector_cb
 - lspg.c, [102](#)
- lspg_lock_detector_done
 - lspg.c, [102](#)
- lspg_lock_detector_init
 - lspg.c, [102](#)
- lspg_lock_detector_struct, [25](#)
 - cond, [26](#)
 - mutex, [26](#)
 - new_value_ready, [26](#)
- lspg_lock_detector_t
 - lspg.c, [93](#)
- lspg_lock_detector_wait
 - lspg.c, [102](#)
- lspg_lock_diffractionmeter
 - lspg.c, [128](#)
- lspg_lock_diffractionmeter_all
 - lspg.c, [103](#)
- lspg_lock_diffractionmeter_call
 - lspg.c, [103](#)
- lspg_lock_diffractionmeter_cb
 - lspg.c, [103](#)
- lspg_lock_diffractionmeter_done
 - lspg.c, [103](#)
- lspg_lock_diffractionmeter_init
 - lspg.c, [104](#)
- lspg_lock_diffractionmeter_struct, [26](#)
 - cond, [26](#)
 - mutex, [26](#)
 - new_value_ready, [26](#)
- lspg_lock_diffractionmeter_t
 - lspg.c, [93](#)
- lspg_lock_diffractionmeter_wait
 - lspg.c, [104](#)
- lspg_next_state
 - lspg.c, [104](#)
- lspg_nextaction_cb
 - lspg.c, [105](#)
- lspg_nextsample
 - lspg.c, [128](#)
 - pgpmac.h, [345](#)
- lspg_nextsample_all
 - lspg.c, [105](#)
 - pgpmac.h, [304](#)
- lspg_nextsample_call
 - lspg.c, [106](#)
- lspg_nextsample_cb
 - lspg.c, [106](#)
- lspg_nextsample_done
 - lspg.c, [107](#)
- lspg_nextsample_init
 - lspg.c, [107](#)
- lspg_nextsample_struct, [27](#)
 - cond, [27](#)
 - mutex, [27](#)
 - new_value_ready, [27](#)
 - nextsample, [27](#)
 - nextsample_isnull, [28](#)
 - no_rows_returned, [28](#)
- lspg_nextsample_t
 - pgpmac.h, [295](#)
- lspg_nextsample_wait
 - lspg.c, [107](#)
- lspg_nextshot
 - lspg.c, [128](#)
 - pgpmac.h, [345](#)
- lspg_nextshot_call
 - lspg.c, [107](#)
 - pgpmac.h, [304](#)
- lspg_nextshot_cb
 - lspg.c, [107](#)
- lspg_nextshot_done
 - lspg.c, [111](#)
 - pgpmac.h, [305](#)
- lspg_nextshot_init

- lspg.c, 111
- lspg_nextshot_struct, 28
 - active, 31
 - active2, 31
 - active2_isnull, 31
 - active_isnull, 31
 - ax, 31
 - ax2, 31
 - ax2_isnull, 31
 - ax_isnull, 31
 - ay, 31
 - ay2, 32
 - ay2_isnull, 32
 - ay_isnull, 32
 - az, 32
 - az2, 32
 - az2_isnull, 32
 - az_isnull, 32
 - cond, 32
 - cx, 32
 - cx2, 32
 - cx2_isnull, 33
 - cx_isnull, 33
 - cy, 33
 - cy2, 33
 - cy2_isnull, 33
 - cy_isnull, 33
 - dsdir, 33
 - dsdir_isnull, 33
 - dsdist, 33
 - dsdist2, 33
 - dsdist2_isnull, 34
 - dsdist_isnull, 34
 - dsexp, 34
 - dsexp2, 34
 - dsexp2_isnull, 34
 - dsexp_isnull, 34
 - dshpid, 34
 - dshpid_isnull, 34
 - dskappa, 34
 - dskappa2, 34
 - dskappa2_isnull, 35
 - dskappa_isnull, 35
 - dsnrg, 35
 - dsnrg2, 35
 - dsnrg2_isnull, 35
 - dsnrg_isnull, 35
 - dsomega, 35
 - dsomega2, 35
 - dsomega2_isnull, 35
 - dsomega_isnull, 35
 - dsoscaxis, 35
 - dsoscaxis2, 36
 - dsoscaxis2_isnull, 36
 - dsoscaxis_isnull, 36
 - dsowidth, 36
 - dsowidth2, 36
 - dsowidth2_isnull, 36
 - dsowidth_isnull, 36
 - dsphi, 36
 - dsphi2, 36
 - dsphi2_isnull, 36
 - dsphi_isnull, 37
 - dspid, 37
 - dspid_isnull, 37
 - mutex, 37
 - new_value_ready, 37
 - no_rows_returned, 37
 - sfn, 37
 - sfn_isnull, 37
 - sindex, 37
 - sindex2, 37
 - sindex2_isnull, 38
 - sindex_isnull, 38
 - skey, 38
 - skey_isnull, 38
 - sstart, 38
 - sstart2, 38
 - sstart2_isnull, 38
 - sstart_isnull, 38
 - stype, 38
 - stype2, 38
 - stype2_isnull, 39
 - stype_isnull, 39
- lspg_nextshot_t
 - pgpmac.h, 295
- lspg_nextshot_wait
 - lspg.c, 112
 - pgpmac.h, 305
- lspg_notice_processor
 - lspg.c, 112
- lspg_pg_connect
 - lspg.c, 112
- lspg_pg_service
 - lspg.c, 113
- lspg_preset_changed_cb
 - lspg.c, 115
- lspg_query_next
 - lspg.c, 115
- lspg_query_push
 - lspg.c, 115
 - pgpmac.h, 305
- lspg_query_queue
 - lspg.c, 128
- lspg_query_queue_off
 - lspg.c, 128
- lspg_query_queue_on
 - lspg.c, 128
- lspg_query_queue_reply
 - lspg.c, 128
- lspg_query_queue_t
 - pgpmac.h, 295
- lspg_query_reply_next
 - lspg.c, 116
- lspg_query_reply_peek
 - lspg.c, 116

- lspg_queue_cond
 - lspg.c, [128](#)
- lspg_queue_mutex
 - lspg.c, [128](#)
- lspg_receive
 - lspg.c, [117](#)
- lspg_resetPoll_response
 - lspg.c, [129](#)
- lspg_run
 - lspg.c, [117](#)
 - pgpmac.h, [306](#)
- lspg_sample_detector_cb
 - lspg.c, [118](#)
- lspg_send_next_query
 - lspg.c, [118](#)
- lspg_seq_run_prep
 - lspg.c, [129](#)
- lspg_seq_run_prep_all
 - lspg.c, [119](#)
 - pgpmac.h, [306](#)
- lspg_seq_run_prep_call
 - lspg.c, [119](#)
- lspg_seq_run_prep_cb
 - lspg.c, [120](#)
- lspg_seq_run_prep_done
 - lspg.c, [120](#)
- lspg_seq_run_prep_init
 - lspg.c, [120](#)
- lspg_seq_run_prep_struct, [39](#)
 - cond, [39](#)
 - mutex, [39](#)
 - new_value_ready, [39](#)
- lspg_seq_run_prep_t
 - lspg.c, [93](#)
- lspg_seq_run_prep_wait
 - lspg.c, [120](#)
- lspg_set_scale_cb
 - lspg.c, [120](#)
- lspg_sig_service
 - lspg.c, [121](#)
- lspg_starttransfer
 - lspg.c, [129](#)
 - pgpmac.h, [345](#)
- lspg_starttransfer_all
 - lspg.c, [121](#)
- lspg_starttransfer_call
 - lspg.c, [122](#)
 - pgpmac.h, [306](#)
- lspg_starttransfer_cb
 - lspg.c, [122](#)
- lspg_starttransfer_done
 - lspg.c, [122](#)
 - pgpmac.h, [307](#)
- lspg_starttransfer_init
 - lspg.c, [122](#)
- lspg_starttransfer_struct, [40](#)
 - cond, [40](#)
 - mutex, [40](#)
 - new_value_ready, [40](#)
 - no_rows_returned, [40](#)
 - starttransfer, [40](#)
- lspg_starttransfer_t
 - pgpmac.h, [295](#)
- lspg_starttransfer_wait
 - lspg.c, [123](#)
 - pgpmac.h, [307](#)
- lspg_thread
 - lspg.c, [129](#)
- lspg_unset_current_preset_moving_cb
 - lspg.c, [123](#)
- lspg_update_kvs_cb
 - lspg.c, [123](#)
- lspg_wait_for_detector
 - lspg.c, [129](#)
- lspg_wait_for_detector_all
 - lspg.c, [124](#)
- lspg_wait_for_detector_call
 - lspg.c, [124](#)
- lspg_wait_for_detector_cb
 - lspg.c, [124](#)
- lspg_wait_for_detector_done
 - lspg.c, [125](#)
- lspg_wait_for_detector_init
 - lspg.c, [125](#)
- lspg_wait_for_detector_struct, [41](#)
 - cond, [41](#)
 - mutex, [41](#)
 - new_value_ready, [41](#)
- lspg_wait_for_detector_t
 - lspg.c, [93](#)
- lspg_wait_for_detector_wait
 - lspg.c, [125](#)
- lspg_waitcryo
 - lspg.c, [129](#)
 - pgpmac.h, [345](#)
- lspg_waitcryo_all
 - lspg.c, [125](#)
 - pgpmac.h, [307](#)
- lspg_waitcryo_cb
 - lspg.c, [126](#)
 - pgpmac.h, [307](#)
- lspg_waitcryo_init
 - lspg.c, [126](#)
- lspg_waitcryo_struct, [41](#)
 - cond, [42](#)
 - mutex, [42](#)
 - new_value_ready, [42](#)
- lspg_waitcryo_t
 - pgpmac.h, [295](#)
- lspg_worker
 - lspg.c, [126](#)
- lspg_zoom_lut_call
 - pgpmac.h, [307](#)
- lspgQueryQueueStruct, [42](#)
 - onResponse, [43](#)
 - qs, [43](#)

- lspgfd
 - lspg.c, [129](#)
- lspmac.c, [130](#)
 - _lspmac_motor_init, [143](#)
 - alignx, [206](#)
 - aligny, [206](#)
 - alignz, [206](#)
 - anal, [206](#)
 - apery, [207](#)
 - aperz, [207](#)
 - arm_parked, [207](#)
 - blight, [207](#)
 - blight_down, [207](#)
 - blight_f, [207](#)
 - blight_ud, [207](#)
 - blight_up, [207](#)
 - copy, [207](#)
 - capz, [208](#)
 - cenx, [208](#)
 - ceny, [208](#)
 - cleanstr, [144](#)
 - cr_cmd, [208](#)
 - cryo, [208](#)
 - cryo_back, [208](#)
 - cryo_switch, [208](#)
 - dbmem, [208](#)
 - dbmemIn, [208](#)
 - dryer, [209](#)
 - etel_init_ok, [209](#)
 - etel_on, [209](#)
 - etel_ready, [209](#)
 - ethCmdOff, [209](#)
 - ethCmdOn, [209](#)
 - ethCmdQueue, [209](#)
 - ethCmdReply, [209](#)
 - flight, [209](#)
 - flight_f, [210](#)
 - flight_oo, [210](#)
 - fluor, [210](#)
 - fluor_back, [210](#)
 - fscint, [210](#)
 - fshut, [210](#)
 - gb_cmd, [210](#)
 - getivars, [210](#)
 - getmvars, [210](#)
 - hex_dump, [144](#)
 - hp_air, [211](#)
 - kappa, [211](#)
 - LS_PMAC_STATE_CR, [139](#)
 - LS_PMAC_STATE_GB, [139](#)
 - LS_PMAC_STATE_GMR, [139](#)
 - LS_PMAC_STATE_IDLE, [139](#)
 - LS_PMAC_STATE_RR, [140](#)
 - LS_PMAC_STATE_SC, [140](#)
 - LS_PMAC_STATE_WACK, [140](#)
 - LS_PMAC_STATE_WCR, [140](#)
 - LS_PMAC_STATE_WGB, [140](#)
 - LSPMAC_MAX_MOTORS, [140](#)
 - LSPMAC_PRESET_REGEX, [140](#)
 - lp_air, [211](#)
 - ls_pmac_state, [211](#)
 - lsConnect, [145](#)
 - lspmac_Error, [150](#)
 - lspmac_GetAllIvars, [163](#)
 - lspmac_GetAllIvarsCB, [163](#)
 - lspmac_GetAllMVars, [163](#)
 - lspmac_GetAllMVarsCB, [163](#)
 - lspmac_GetShortReplyCB, [165](#)
 - lspmac_Getmem, [164](#)
 - lspmac_GetmemReplyCB, [164](#)
 - lspmac_Reset, [189](#)
 - lspmac_SendControlReplyPrintCB, [196](#)
 - lspmac_Service, [196](#)
 - lspmac_SockFlush, [201](#)
 - lspmac_SockGetmem, [201](#)
 - lspmac_SockSendControlCharPrint, [201](#)
 - lspmac_SockSendDPControlChar, [202](#)
 - lspmac_SockSendDPControlCharCB, [202](#)
 - lspmac_SockSendDPLine, [202](#)
 - lspmac_SockSendDPQueue, [202](#)
 - lspmac_SockSendline, [203](#)
 - lspmac_SockSendline_nr, [203](#)
 - lspmac_abort, [145](#)
 - lspmac_ascii_buffers, [211](#)
 - lspmac_ascii_buffers_mutex, [211](#)
 - lspmac_ascii_buffers_t, [143](#)
 - lspmac_ascii_busy, [211](#)
 - lspmac_ascii_mutex, [211](#)
 - lspmac_asciicmdCB, [146](#)
 - lspmac_backLight_down_cb, [146](#)
 - lspmac_backLight_up_cb, [146](#)
 - lspmac_bi_init, [146](#)
 - lspmac_bis, [211](#)
 - lspmac_blight_lut_setup, [147](#)
 - lspmac_bo_init, [147](#)
 - lspmac_bo_read, [148](#)
 - lspmac_combined_move_t, [143](#)
 - lspmac_command_done_cb, [148](#)
 - lspmac_cryoSwitchChanged_cb, [149](#)
 - lspmac_dac_init, [149](#)
 - lspmac_dac_read, [149](#)
 - lspmac_dpascii_off, [211](#)
 - lspmac_dpascii_on, [212](#)
 - lspmac_dpascii_queue, [212](#)
 - lspmac_dpascii_queue_t, [143](#)
 - lspmac_est_move_time, [150](#)
 - lspmac_est_move_time_wait, [155](#)
 - lspmac_find_motor_by_name, [156](#)
 - lspmac_flight_lut_setup, [157](#)
 - lspmac_fscint_lut_setup, [157](#)
 - lspmac_fshut_init, [157](#)
 - lspmac_get_ascii, [158](#)
 - lspmac_get_ascii_cb, [158](#)
 - lspmac_get_status, [160](#)
 - lspmac_get_status_cb, [160](#)
 - lspmac_getBIPosition, [164](#)

- [lspmac_getPosition](#), 165
- [lspmac_home1_queue](#), 165
- [lspmac_home2_queue](#), 167
- [lspmac_init](#), 167
- [lspmac_jogabs_queue](#), 171
- [lspmac_light_zoom_cb](#), 171
- [lspmac_lut](#), 172
- [lspmac_more_ascii_cb](#), 173
- [lspmac_motor_init](#), 173
- [lspmac_motors](#), 212
- [lspmac_move_or_jog_abs_queue](#), 174
- [lspmac_move_or_jog_preset_queue](#), 177
- [lspmac_move_preset_queue](#), 177
- [lspmac_moveabs_blight_factor_queue](#), 178
- [lspmac_moveabs_bo_queue](#), 178
- [lspmac_moveabs_flight_factor_queue](#), 178
- [lspmac_moveabs_frontlight_oo_queue](#), 179
- [lspmac_moveabs_fshut_queue](#), 179
- [lspmac_moveabs_queue](#), 180
- [lspmac_moveabs_timed_queue](#), 180
- [lspmac_moveabs_wait](#), 181
- [lspmac_movedac_queue](#), 182
- [lspmac_movezoom_queue](#), 183
- [lspmac_moving_cond](#), 212
- [lspmac_moving_flags](#), 212
- [lspmac_moving_mutex](#), 212
- [lspmac_nbis](#), 212
- [lspmac_next_state](#), 183
- [lspmac_nmotors](#), 212
- [lspmac_pmacmotor_read](#), 185
- [lspmac_pop_queue](#), 188
- [lspmac_pop_reply](#), 189
- [lspmac_push_queue](#), 189
- [lspmac_reset_queue](#), 190
- [lspmac_rlut](#), 190
- [lspmac_run](#), 191
- [lspmac_scint_dried_cb](#), 192
- [lspmac_scint_maybe_move_sample_cb](#), 193
- [lspmac_scint_maybe_return_sample_cb](#), 193
- [lspmac_scint_maybe_turn_off_dryer_cb](#), 193
- [lspmac_scint_maybe_turn_on_dryer_cb](#), 194
- [lspmac_send_command](#), 194
- [lspmac_sendcmd](#), 195
- [lspmac_sendcmd_nocb](#), 196
- [lspmac_set_motion_flags](#), 199
- [lspmac_shutter_cond](#), 212
- [lspmac_shutter_has_opened](#), 212
- [lspmac_shutter_mutex](#), 213
- [lspmac_shutter_read](#), 200
- [lspmac_shutter_state](#), 213
- [lspmac_soft_motor_init](#), 204
- [lspmac_soft_motor_read](#), 204
- [lspmac_status_last_time](#), 213
- [lspmac_status_time](#), 213
- [lspmac_test_preset](#), 204
- [lspmac_video_rotate](#), 204
- [lspmac_worker](#), 205
- [lspmac_zoom_lut_setup](#), 206
- [md2_status](#), 213
- [md2_status_mutex](#), 213
- [md2_status_t](#), 143
- [minikappa_ok](#), 213
- [motors_ht](#), 213
- [now](#), 213
- [omega](#), 214
- [omega_zero_search](#), 214
- [omega_zero_time](#), 214
- [omega_zero_velocity](#), 214
- [PMAC_MIN_CMD_TIME](#), 141
- [PMACPORT](#), 141
- [phi](#), 214
- [pmac_cmd_size](#), 141
- [pmac_error_strs](#), 214
- [pmac_queue_cond](#), 215
- [pmac_queue_mutex](#), 215
- [pmac_thread](#), 215
- [pmacfd](#), 215
- [rr_cmd](#), 215
- [sample_detected](#), 215
- [scint](#), 215
- [shutter_open](#), 215
- [smart_mag_err](#), 215
- [smart_mag_off](#), 215
- [smart_mag_on](#), 216
- [smart_mag_oo](#), 216
- [VR_CTRL_RESPONSE](#), 141
- [VR_DOWNLOAD](#), 141
- [VR_FWDOWNLOAD](#), 141
- [VR_IPADDRESS](#), 141
- [VR_PMAC_FLUSH](#), 141
- [VR_PMAC_GETBUFFER](#), 141
- [VR_PMAC_GETLINE](#), 141
- [VR_PMAC_GETMEM](#), 141
- [VR_PMAC_GETRESPONSE](#), 142
- [VR_PMAC_PORT](#), 142
- [VR_PMAC_READREADY](#), 142
- [VR_PMAC_SENDLINE](#), 142
- [VR_PMAC_SETBIT](#), 142
- [VR_PMAC_SETBITS](#), 142
- [VR_PMAC_SETMEM](#), 142
- [VR_PMAC_WRITEBUFFER](#), 142
- [VR_PMAC_WRITEERROR](#), 142
- [VR_UPLOAD](#), 142
- [zoom](#), 216
- [lspmac_Error](#)
 - [lspmac.c](#), 150
- [lspmac_GetAllIVars](#)
 - [lspmac.c](#), 163
- [lspmac_GetAllIVarsCB](#)
 - [lspmac.c](#), 163
- [lspmac_GetAllMVars](#)
 - [lspmac.c](#), 163
- [lspmac_GetAllMVarsCB](#)
 - [lspmac.c](#), 163
- [lspmac_GetShortReplyCB](#)
 - [lspmac.c](#), 165

`Ispmac_Getmem`
 `Ispmac.c`, 164
`Ispmac_GetmemReplyCB`
 `Ispmac.c`, 164
`Ispmac_Reset`
 `Ispmac.c`, 189
`Ispmac_SendControlReplyPrintCB`
 `Ispmac.c`, 196
`Ispmac_Service`
 `Ispmac.c`, 196
`Ispmac_SockFlush`
 `Ispmac.c`, 201
`Ispmac_SockGetmem`
 `Ispmac.c`, 201
`Ispmac_SockSendControlCharPrint`
 `Ispmac.c`, 201
`Ispmac_SockSendDPControlChar`
 `Ispmac.c`, 202
 `pgpmac.h`, 328
`Ispmac_SockSendDPControlCharCB`
 `Ispmac.c`, 202
`Ispmac_SockSendDPLine`
 `Ispmac.c`, 202
 `pgpmac.h`, 328
`Ispmac_SockSendDPQueue`
 `Ispmac.c`, 202
`Ispmac_SockSendline`
 `Ispmac.c`, 203
 `pgpmac.h`, 329
`Ispmac_SockSendline_nr`
 `Ispmac.c`, 203
`Ispmac_abort`
 `Ispmac.c`, 145
 `pgpmac.h`, 308
`Ispmac_ascii_buffers`
 `Ispmac.c`, 211
`Ispmac_ascii_buffers_mutex`
 `Ispmac.c`, 211
`Ispmac_ascii_buffers_struct`, 43
 `command_buf`, 43
 `command_buf_cc`, 43
 `command_str`, 43
 `response_buf`, 44
 `response_n`, 44
 `response_str`, 44
`Ispmac_ascii_buffers_t`
 `Ispmac.c`, 143
`Ispmac_ascii_busy`
 `Ispmac.c`, 211
`Ispmac_ascii_mutex`
 `Ispmac.c`, 211
`Ispmac_asciicmdCB`
 `Ispmac.c`, 146
`Ispmac_backLight_down_cb`
 `Ispmac.c`, 146
`Ispmac_backLight_up_cb`
 `Ispmac.c`, 146
`Ispmac_bi_init`
 `Ispmac.c`, 146
`Ispmac_bi_struct`, 44
 `changeEventOff`, 45
 `changeEventOn`, 45
 `first_time`, 45
 `mask`, 45
 `mutex`, 45
 `position`, 45
 `previous`, 45
 `ptr`, 45
`Ispmac_bi_t`
 `pgpmac.h`, 295
`Ispmac_bis`
 `Ispmac.c`, 211
`Ispmac_blight_lut_setup`
 `Ispmac.c`, 147
`Ispmac_bo_init`
 `Ispmac.c`, 147
`Ispmac_bo_read`
 `Ispmac.c`, 148
`Ispmac_cmd_queue_struct`, 46
 `event`, 46
 `no_reply`, 46
 `onResponse`, 46
 `pcmd`, 46
 `time_sent`, 46
`Ispmac_combined_move_struct`, 47
 `axis`, 47
 `coord_num`, 47
 `Delta`, 47
 `moveme`, 47
`Ispmac_combined_move_t`
 `Ispmac.c`, 143
`Ispmac_command_done_cb`
 `Ispmac.c`, 148
`Ispmac_cryoSwitchChanged_cb`
 `Ispmac.c`, 149
`Ispmac_dac_init`
 `Ispmac.c`, 149
`Ispmac_dac_read`
 `Ispmac.c`, 149
`Ispmac_dpascii_off`
 `Ispmac.c`, 211
`Ispmac_dpascii_on`
 `Ispmac.c`, 212
`Ispmac_dpascii_queue`
 `Ispmac.c`, 212
`Ispmac_dpascii_queue_struct`, 47
 `event`, 48
 `pl`, 48
`Ispmac_dpascii_queue_t`
 `Ispmac.c`, 143
`Ispmac_est_move_time`
 `Ispmac.c`, 150
 `pgpmac.h`, 308
`Ispmac_est_move_time_wait`
 `Ispmac.c`, 155
 `pgpmac.h`, 313

- lspmac_find_motor_by_name
 - lspmac.c, [156](#)
 - pgpmac.h, [314](#)
- lspmac_flight_lut_setup
 - lspmac.c, [157](#)
- lspmac_fscint_lut_setup
 - lspmac.c, [157](#)
- lspmac_fshut_init
 - lspmac.c, [157](#)
- lspmac_get_ascii
 - lspmac.c, [158](#)
- lspmac_get_ascii_cb
 - lspmac.c, [158](#)
- lspmac_get_status
 - lspmac.c, [160](#)
- lspmac_get_status_cb
 - lspmac.c, [160](#)
- lspmac_getBIPosition
 - lspmac.c, [164](#)
 - pgpmac.h, [314](#)
- lspmac_getPosition
 - lspmac.c, [165](#)
 - pgpmac.h, [314](#)
- lspmac_home1_queue
 - lspmac.c, [165](#)
 - pgpmac.h, [314](#)
- lspmac_home2_queue
 - lspmac.c, [167](#)
 - pgpmac.h, [316](#)
- lspmac_init
 - lspmac.c, [167](#)
 - pgpmac.h, [316](#)
- lspmac_jogabs_queue
 - lspmac.c, [171](#)
 - pgpmac.h, [320](#)
- lspmac_light_zoom_cb
 - lspmac.c, [171](#)
- lspmac_lut
 - lspmac.c, [172](#)
- lspmac_more_ascii_cb
 - lspmac.c, [173](#)
- lspmac_motor_init
 - lspmac.c, [173](#)
- lspmac_motor_struct, [48](#)
 - active, [50](#)
 - active_init, [50](#)
 - actual_pos_cnts, [50](#)
 - actual_pos_cnts_p, [51](#)
 - axis, [51](#)
 - command_sent, [51](#)
 - cond, [51](#)
 - coord_num, [51](#)
 - dac_mvar, [51](#)
 - home, [51](#)
 - homing, [51](#)
 - in_position_band, [51](#)
 - inactive_init, [52](#)
 - jogAbs, [52](#)
 - lut, [52](#)
 - magic, [52](#)
 - max_accel, [52](#)
 - max_pos, [52](#)
 - max_speed, [52](#)
 - min_pos, [52](#)
 - motion_seen, [52](#)
 - motor_num, [53](#)
 - moveAbs, [53](#)
 - mutex, [53](#)
 - name, [53](#)
 - neg_limit_hit, [53](#)
 - neutral_pos, [53](#)
 - nlut, [53](#)
 - not_done, [53](#)
 - pos_limit_hit, [53](#)
 - position, [54](#)
 - pq, [54](#)
 - precision, [54](#)
 - printf_fmt, [54](#)
 - read, [54](#)
 - read_mask, [54](#)
 - read_ptr, [54](#)
 - redis_fmt, [54](#)
 - redis_position, [54](#)
 - reported_pg_position, [55](#)
 - reported_position, [55](#)
 - requested_pos_cnts, [55](#)
 - requested_position, [55](#)
 - status1, [55](#)
 - status1_p, [55](#)
 - status2, [55](#)
 - status2_p, [55](#)
 - status_str, [55](#)
 - u2c, [56](#)
 - unit, [56](#)
 - update_resolution, [56](#)
 - win, [56](#)
 - write_fmt, [56](#)
- lspmac_motor_t
 - pgpmac.h, [295](#)
- lspmac_motors
 - lspmac.c, [212](#)
 - pgpmac.h, [345](#)
- lspmac_move_or_jog_abs_queue
 - lspmac.c, [174](#)
 - pgpmac.h, [320](#)
- lspmac_move_or_jog_preset_queue
 - lspmac.c, [177](#)
 - pgpmac.h, [323](#)
- lspmac_move_or_jog_queue
 - pgpmac.h, [323](#)
- lspmac_move_preset_queue
 - lspmac.c, [177](#)
 - pgpmac.h, [324](#)
- lspmac_moveabs_blight_factor_queue
 - lspmac.c, [178](#)
- lspmac_moveabs_bo_queue

- [lspmac.c, 178](#)
- [lspmac_moveabs_flight_factor_queue](#)
 - [lspmac.c, 178](#)
- [lspmac_moveabs_frontlight_oo_queue](#)
 - [lspmac.c, 179](#)
- [lspmac_moveabs_fshut_queue](#)
 - [lspmac.c, 179](#)
- [lspmac_moveabs_queue](#)
 - [lspmac.c, 180](#)
 - [pgpmac.h, 324](#)
- [lspmac_moveabs_timed_queue](#)
 - [lspmac.c, 180](#)
- [lspmac_moveabs_wait](#)
 - [lspmac.c, 181](#)
 - [pgpmac.h, 324](#)
- [lspmac_movedac_queue](#)
 - [lspmac.c, 182](#)
- [lspmac_movezoom_queue](#)
 - [lspmac.c, 183](#)
- [lspmac_moving_cond](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 345](#)
- [lspmac_moving_flags](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 345](#)
- [lspmac_moving_mutex](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 346](#)
- [lspmac_nbis](#)
 - [lspmac.c, 212](#)
- [lspmac_next_state](#)
 - [lspmac.c, 183](#)
- [lspmac_nmotors](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 346](#)
- [lspmac_pmacmotor_read](#)
 - [lspmac.c, 185](#)
- [lspmac_pop_queue](#)
 - [lspmac.c, 188](#)
- [lspmac_pop_reply](#)
 - [lspmac.c, 189](#)
- [lspmac_push_queue](#)
 - [lspmac.c, 189](#)
- [lspmac_reset_queue](#)
 - [lspmac.c, 190](#)
- [lspmac_rlut](#)
 - [lspmac.c, 190](#)
- [lspmac_run](#)
 - [lspmac.c, 191](#)
 - [pgpmac.h, 325](#)
- [lspmac_scint_dried_cb](#)
 - [lspmac.c, 192](#)
- [lspmac_scint_maybe_move_sample_cb](#)
 - [lspmac.c, 193](#)
- [lspmac_scint_maybe_return_sample_cb](#)
 - [lspmac.c, 193](#)
- [lspmac_scint_maybe_turn_off_dryer_cb](#)
 - [lspmac.c, 193](#)
- [lspmac_scint_maybe_turn_on_dryer_cb](#)
 - [lspmac.c, 194](#)
- [lspmac_send_command](#)
 - [lspmac.c, 194](#)
- [lspmac_sendcmd](#)
 - [lspmac.c, 195](#)
- [lspmac_sendcmd_nocb](#)
 - [lspmac.c, 196](#)
- [lspmac_set_motion_flags](#)
 - [lspmac.c, 199](#)
 - [pgpmac.h, 327](#)
- [lspmac_shutter_cond](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 346](#)
- [lspmac_shutter_has_opened](#)
 - [lspmac.c, 212](#)
 - [pgpmac.h, 346](#)
- [lspmac_shutter_mutex](#)
 - [lspmac.c, 213](#)
 - [pgpmac.h, 346](#)
- [lspmac_shutter_read](#)
 - [lspmac.c, 200](#)
- [lspmac_shutter_state](#)
 - [lspmac.c, 213](#)
 - [pgpmac.h, 346](#)
- [lspmac_soft_motor_init](#)
 - [lspmac.c, 204](#)
- [lspmac_soft_motor_read](#)
 - [lspmac.c, 204](#)
- [lspmac_status_last_time](#)
 - [lspmac.c, 213](#)
- [lspmac_status_time](#)
 - [lspmac.c, 213](#)
- [lspmac_test_preset](#)
 - [lspmac.c, 204](#)
- [lspmac_video_rotate](#)
 - [lspmac.c, 204](#)
 - [pgpmac.h, 329](#)
- [lspmac_worker](#)
 - [lspmac.c, 205](#)
- [lspmac_zoom_lut_setup](#)
 - [lspmac.c, 206](#)
- [lsredis.c, 216](#)
 - [_lsredis_get_obj, 219](#)
 - [_lsredis_set_value, 220](#)
 - [lsredis_addRead, 221](#)
 - [lsredis_addWrite, 221](#)
 - [lsredis_cleanup, 222](#)
 - [lsredis_cmpnstr, 222](#)
 - [lsredis_cmpstr, 222](#)
 - [lsredis_cond, 236](#)
 - [lsredis_debugCB, 222](#)
 - [lsredis_delRead, 223](#)
 - [lsredis_delWrite, 223](#)
 - [lsredis_fd_service, 224](#)
 - [lsredis_find_preset, 224](#)
 - [lsredis_find_preset_index_by_position, 224](#)
 - [lsredis_get_obj, 225](#)

- lsredis_get_or_set_d, 225
- lsredis_get_or_set_l, 226
- lsredis_get_string_array, 226
- lsredis_getb, 226
- lsredis_getc, 227
- lsredis_getd, 227
- lsredis_getl, 227
- lsredis_getstr, 227
- lsredis_head, 236
- lsredis_hgetCB, 228
- lsredis_htab, 236
- lsredis_init, 228
- lsredis_key_select_regex, 237
- lsredis_keysCB, 229
- lsredis_load_presets, 230
- lsredis_maybe_add_key, 231
- lsredis_mutex, 237
- lsredis_objs, 237
- lsredis_preset_ht, 237
- lsredis_preset_list, 237
- lsredis_preset_list_mutex, 237
- lsredis_preset_list_t, 219
- lsredis_preset_max_n, 237
- lsredis_preset_n, 237
- lsredis_publisher, 237
- lsredis_regexec, 231
- lsredis_run, 231
- lsredis_running, 237
- lsredis_set_preset, 231
- lsredis_set_value, 232
- lsredis_setstr, 232
- lsredis_sig_service, 233
- lsredis_subCB, 234
- lsredis_thread, 237
- lsredis_worker, 235
- redisDisconnectCB, 236
- roac, 237
- rofd, 238
- subac, 238
- subfd, 238
- wrac, 238
- wrfd, 238
- lsredis_addRead
 - lsredis.c, 221
- lsredis_addWrite
 - lsredis.c, 221
- lsredis_cleanup
 - lsredis.c, 222
- lsredis_cmpnstr
 - lsredis.c, 222
 - pgpmac.h, 330
- lsredis_cmpstr
 - lsredis.c, 222
 - pgpmac.h, 330
- lsredis_cond
 - lsredis.c, 236
 - pgpmac.h, 346
- lsredis_debugCB
 - lsredis.c, 222
- lsredis_delRead
 - lsredis.c, 223
- lsredis_delWrite
 - lsredis.c, 223
- lsredis_fd_service
 - lsredis.c, 224
- lsredis_find_preset
 - lsredis.c, 224
 - pgpmac.h, 330
- lsredis_find_preset_index_by_position
 - lsredis.c, 224
 - pgpmac.h, 331
- lsredis_get_obj
 - lsredis.c, 225
 - pgpmac.h, 331
- lsredis_get_or_set_d
 - lsredis.c, 225
- lsredis_get_or_set_l
 - lsredis.c, 226
- lsredis_get_string_array
 - lsredis.c, 226
 - pgpmac.h, 332
- lsredis_getb
 - lsredis.c, 226
 - pgpmac.h, 332
- lsredis_getc
 - lsredis.c, 227
 - pgpmac.h, 332
- lsredis_getd
 - lsredis.c, 227
 - pgpmac.h, 332
- lsredis_getl
 - lsredis.c, 227
 - pgpmac.h, 332
- lsredis_getstr
 - lsredis.c, 227
 - pgpmac.h, 333
- lsredis_head
 - lsredis.c, 236
- lsredis_hgetCB
 - lsredis.c, 228
- lsredis_htab
 - lsredis.c, 236
- lsredis_init
 - lsredis.c, 228
 - pgpmac.h, 333
- lsredis_key_select_regex
 - lsredis.c, 237
- lsredis_keysCB
 - lsredis.c, 229
- lsredis_load_presets
 - lsredis.c, 230
 - pgpmac.h, 334
- lsredis_maybe_add_key
 - lsredis.c, 231
- lsredis_mutex
 - lsredis.c, 237

- pgpmac.h, 346
- lsredis_obj_struct, 56
 - avalue, 57
 - bvalue, 57
 - cond, 57
 - cvalue, 57
 - dvalue, 57
 - events_name, 58
 - hits, 58
 - key, 58
 - lvalue, 58
 - mutex, 58
 - next, 58
 - valid, 58
 - value, 58
 - value_length, 58
 - wait_for_me, 59
- lsredis_obj_t
 - pgpmac.h, 295
- lsredis_objs
 - lsredis.c, 237
- lsredis_preset_ht
 - lsredis.c, 237
- lsredis_preset_list
 - lsredis.c, 237
- lsredis_preset_list_mutex
 - lsredis.c, 237
- lsredis_preset_list_struct, 59
 - index, 59
 - key, 59
 - name, 59
 - next, 59
 - position, 59
- lsredis_preset_list_t
 - lsredis.c, 219
- lsredis_preset_max_n
 - lsredis.c, 237
- lsredis_preset_n
 - lsredis.c, 237
- lsredis_publisher
 - lsredis.c, 237
- lsredis_regexexec
 - lsredis.c, 231
 - pgpmac.h, 335
- lsredis_run
 - lsredis.c, 231
 - pgpmac.h, 336
- lsredis_running
 - lsredis.c, 237
 - pgpmac.h, 346
- lsredis_set_preset
 - lsredis.c, 231
 - pgpmac.h, 336
- lsredis_set_value
 - lsredis.c, 232
- lsredis_setstr
 - lsredis.c, 232
 - pgpmac.h, 336
- lsredis_sig_service
 - lsredis.c, 233
- lsredis_subCB
 - lsredis.c, 234
- lsredis_thread
 - lsredis.c, 237
- lsredis_worker
 - lsredis.c, 235
- lstest.c, 238
 - lstest_lspmac_est_move_time, 238
 - lstest_main, 240
- lstest_lspmac_est_move_time
 - lstest.c, 238
- lstest_main
 - lstest.c, 240
 - pgpmac.h, 337
- lstimer.c, 240
 - handler, 242
 - LSTIMER_LIST_LENGTH, 241
 - lstimer_active_timers, 246
 - lstimer_cond, 246
 - lstimer_init, 242
 - lstimer_list, 246
 - lstimer_list_t, 242
 - lstimer_mutex, 246
 - lstimer_run, 242
 - lstimer_set_timer, 242
 - lstimer_thread, 246
 - lstimer_timerid, 246
 - lstimer_unset_timer, 243
 - lstimer_worker, 244
 - new_timer, 246
 - service_timers, 245
- lstimer_active_timers
 - lstimer.c, 246
- lstimer_cond
 - lstimer.c, 246
- lstimer_init
 - lstimer.c, 242
 - pgpmac.h, 337
- lstimer_list
 - lstimer.c, 246
- lstimer_list_struct, 60
 - delay_nsecs, 60
 - delay_secs, 60
 - event, 61
 - init_nsecs, 61
 - init_secs, 61
 - last_nsecs, 61
 - last_secs, 61
 - ncalls, 61
 - next_nsecs, 61
 - next_secs, 61
 - shots, 61
- lstimer_list_t
 - lstimer.c, 242
- lstimer_mutex
 - lstimer.c, 246

- lsterimer_run
 - lsterimer.c, 242
 - pgpmac.h, 338
- lsterimer_set_timer
 - lsterimer.c, 242
 - pgpmac.h, 338
- lsterimer_thread
 - lsterimer.c, 246
- lsterimer_timerid
 - lsterimer.c, 246
- lsterimer_unset_timer
 - lsterimer.c, 243
 - pgpmac.h, 339
- lsterimer_worker
 - lsterimer.c, 244
- lupdate_init
 - pgpmac.h, 339
- lupdate_run
 - pgpmac.h, 339
- ltime
 - lslogging_queue_struct, 21
- lut
 - lspmac_motor_struct, 52
- lvalue
 - lsredis_obj_struct, 58
- MD2CMDSD_CMD_LENGTH
 - pgpmac.h, 295
- magic
 - lspmac_motor_struct, 52
- main
 - pgpmac.c, 282
- mask
 - lspmac_bi_struct, 45
- max_accel
 - lspmac_motor_struct, 52
- max_pos
 - lspmac_motor_struct, 52
- max_speed
 - lspmac_motor_struct, 52
- md2_status
 - lspmac.c, 213
- md2_status_mutex
 - lspmac.c, 213
 - pgpmac.h, 346
- md2_status_t
 - lspmac.c, 143
- md2StatusStruct, 62
 - acc11c_1, 64
 - acc11c_2, 64
 - acc11c_3, 64
 - acc11c_5, 64
 - acc11c_6, 64
 - alignx_act_pos, 64
 - alignx_status_1, 64
 - alignx_status_2, 64
 - aligny_act_pos, 64
 - aligny_status_1, 64
 - aligny_status_2, 65
 - alignz_act_pos, 65
 - alignz_status_1, 65
 - alignz_status_2, 65
 - analyzer_act_pos, 65
 - analyzer_status_1, 65
 - analyzer_status_2, 65
 - aperturey_act_pos, 65
 - aperturey_status_1, 65
 - aperturey_status_2, 65
 - aperturez_act_pos, 65
 - aperturez_status_1, 65
 - aperturez_status_2, 66
 - back_dac, 66
 - copy_act_pos, 66
 - copy_status_1, 66
 - copy_status_2, 66
 - capz_act_pos, 66
 - capz_status_1, 66
 - capz_status_2, 66
 - centerx_act_pos, 66
 - centerx_status_1, 66
 - centerx_status_2, 66
 - centery_act_pos, 66
 - centery_status_1, 67
 - centery_status_2, 67
 - dummy1, 67
 - dummy2, 67
 - dummy3, 67
 - dummy4, 67
 - dummy5, 67
 - dummy6, 67
 - dummy7, 67
 - dummy8, 67
 - dummy9, 67
 - dummyA, 67
 - dummyB, 68
 - front_dac, 68
 - fs_has_opened, 68
 - fs_has_opened_globally, 68
 - fs_is_open, 68
 - kappa_act_pos, 68
 - kappa_status_1, 68
 - kappa_status_2, 68
 - moving_flags, 68
 - number_passes, 68
 - omega_act_pos, 68
 - omega_status_1, 68
 - omega_status_2, 69
 - phi_act_pos, 69
 - phi_status_1, 69
 - phi_status_2, 69
 - phiscan, 69
 - scint_act_pos, 69
 - scint_piezo, 69
 - scint_status_1, 69
 - scint_status_2, 69
 - zoom_act_pos, 69
 - zoom_status_1, 69

- zoom_status_2, [69](#)
- md2cmds.c, [246](#)
 - md2cmds_abort, [249](#)
 - md2cmds_action_queue, [250](#)
 - md2cmds_action_wait, [250](#)
 - md2cmds_capz_moving_time, [278](#)
 - md2cmds_center, [250](#)
 - md2cmds_cmd, [278](#)
 - md2cmds_cmd_kv_t, [249](#)
 - md2cmds_cmd_kvs, [279](#)
 - md2cmds_cmd_regex, [279](#)
 - md2cmds_collect, [251](#)
 - md2cmds_cond, [279](#)
 - md2cmds_coordsys_1_stopped_cb, [255](#)
 - md2cmds_coordsys_2_stopped_cb, [255](#)
 - md2cmds_coordsys_3_stopped_cb, [255](#)
 - md2cmds_coordsys_4_stopped_cb, [255](#)
 - md2cmds_coordsys_5_stopped_cb, [255](#)
 - md2cmds_coordsys_7_stopped_cb, [255](#)
 - md2cmds_hmap, [279](#)
 - md2cmds_home_prep, [256](#)
 - md2cmds_home_wait, [256](#)
 - md2cmds_homing_cond, [279](#)
 - md2cmds_homing_count, [279](#)
 - md2cmds_homing_mutex, [279](#)
 - md2cmds_init, [256](#)
 - md2cmds_is_moving, [257](#)
 - md2cmds_kappaphi_move, [257](#)
 - md2cmds_maybe_done_homing_cb, [258](#)
 - md2cmds_maybe_done_moving_cb, [258](#)
 - md2cmds_maybe_rotate_done_cb, [259](#)
 - md2cmds_md_status_code, [279](#)
 - md2cmds_move_prep, [259](#)
 - md2cmds_move_wait, [259](#)
 - md2cmds_moveAbs, [260](#)
 - md2cmds_moveRel, [261](#)
 - md2cmds_moving_cond, [280](#)
 - md2cmds_moving_count, [280](#)
 - md2cmds_moving_mutex, [280](#)
 - md2cmds_moving_queue_wait, [280](#)
 - md2cmds_mutex, [280](#)
 - md2cmds_mvcenter_move, [262](#)
 - md2cmds_organs_move_presets, [262](#)
 - md2cmds_phase_beamLocation, [263](#)
 - md2cmds_phase_center, [264](#)
 - md2cmds_phase_change, [264](#)
 - md2cmds_phase_dataCollection, [266](#)
 - md2cmds_phase_manualMount, [266](#)
 - md2cmds_phase_robotMount, [267](#)
 - md2cmds_phase_safe, [268](#)
 - md2cmds_prep_axis, [268](#)
 - md2cmds_rotate, [269](#)
 - md2cmds_rotate_cb, [271](#)
 - md2cmds_run, [271](#)
 - md2cmds_run_cmd, [271](#)
 - md2cmds_set, [272](#)
 - md2cmds_set_scale_cb, [273](#)
 - md2cmds_settransferpoint, [274](#)
 - md2cmds_test, [274](#)
 - md2cmds_thread, [280](#)
 - md2cmds_time_capz_cb, [274](#)
 - md2cmds_transfer, [275](#)
 - md2cmds_worker, [277](#)
 - rotating, [280](#)
- md2cmds_abort
 - md2cmds.c, [249](#)
- md2cmds_action_queue
 - md2cmds.c, [250](#)
- md2cmds_action_wait
 - md2cmds.c, [250](#)
- md2cmds_capz_moving_time
 - md2cmds.c, [278](#)
- md2cmds_center
 - md2cmds.c, [250](#)
- md2cmds_cmd
 - md2cmds.c, [278](#)
 - pgpmac.h, [347](#)
- md2cmds_cmd_kv_struct, [62](#)
 - k, [62](#)
 - v, [62](#)
- md2cmds_cmd_kv_t
 - md2cmds.c, [249](#)
- md2cmds_cmd_kvs
 - md2cmds.c, [279](#)
- md2cmds_cmd_regex
 - md2cmds.c, [279](#)
- md2cmds_collect
 - md2cmds.c, [251](#)
- md2cmds_cond
 - md2cmds.c, [279](#)
 - pgpmac.h, [347](#)
- md2cmds_coordsys_1_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_coordsys_2_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_coordsys_3_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_coordsys_4_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_coordsys_5_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_coordsys_7_stopped_cb
 - md2cmds.c, [255](#)
- md2cmds_hmap
 - md2cmds.c, [279](#)
- md2cmds_home_prep
 - md2cmds.c, [256](#)
- md2cmds_home_wait
 - md2cmds.c, [256](#)
- md2cmds_homing_cond
 - md2cmds.c, [279](#)
- md2cmds_homing_count
 - md2cmds.c, [279](#)
- md2cmds_homing_mutex
 - md2cmds.c, [279](#)
- md2cmds_init

- md2cmds.c, [256](#)
- pgpmac.h, [339](#)
- md2cmds_is_moving
 - md2cmds.c, [257](#)
- md2cmds_kappaphi_move
 - md2cmds.c, [257](#)
- md2cmds_maybe_done_homing_cb
 - md2cmds.c, [258](#)
- md2cmds_maybe_done_moving_cb
 - md2cmds.c, [258](#)
- md2cmds_maybe_rotate_done_cb
 - md2cmds.c, [259](#)
- md2cmds_md_status_code
 - md2cmds.c, [279](#)
 - pgpmac.h, [347](#)
- md2cmds_move_prep
 - md2cmds.c, [259](#)
- md2cmds_move_wait
 - md2cmds.c, [259](#)
- md2cmds_moveAbs
 - md2cmds.c, [260](#)
- md2cmds_moveRel
 - md2cmds.c, [261](#)
- md2cmds_moving_cond
 - md2cmds.c, [280](#)
- md2cmds_moving_count
 - md2cmds.c, [280](#)
- md2cmds_moving_mutex
 - md2cmds.c, [280](#)
- md2cmds_moving_queue_wait
 - md2cmds.c, [280](#)
- md2cmds_mutex
 - md2cmds.c, [280](#)
 - pgpmac.h, [347](#)
- md2cmds_mvcenter_move
 - md2cmds.c, [262](#)
- md2cmds_organs_move_presets
 - md2cmds.c, [262](#)
- md2cmds_pg_cond
 - pgpmac.h, [347](#)
- md2cmds_pg_mutex
 - pgpmac.h, [347](#)
- md2cmds_phase_beamLocation
 - md2cmds.c, [263](#)
- md2cmds_phase_center
 - md2cmds.c, [264](#)
- md2cmds_phase_change
 - md2cmds.c, [264](#)
- md2cmds_phase_dataCollection
 - md2cmds.c, [266](#)
- md2cmds_phase_manualMount
 - md2cmds.c, [266](#)
- md2cmds_phase_robotMount
 - md2cmds.c, [267](#)
- md2cmds_phase_safe
 - md2cmds.c, [268](#)
- md2cmds_prep_axis
 - md2cmds.c, [268](#)
- md2cmds_rotate
 - md2cmds.c, [269](#)
- md2cmds_rotate_cb
 - md2cmds.c, [271](#)
- md2cmds_run
 - md2cmds.c, [271](#)
 - pgpmac.h, [340](#)
- md2cmds_run_cmd
 - md2cmds.c, [271](#)
- md2cmds_set
 - md2cmds.c, [272](#)
- md2cmds_set_scale_cb
 - md2cmds.c, [273](#)
- md2cmds_settransferpoint
 - md2cmds.c, [274](#)
- md2cmds_test
 - md2cmds.c, [274](#)
- md2cmds_thread
 - md2cmds.c, [280](#)
- md2cmds_time_capz_cb
 - md2cmds.c, [274](#)
- md2cmds_transfer
 - md2cmds.c, [275](#)
- md2cmds_worker
 - md2cmds.c, [277](#)
- min_pos
 - lspmac_motor_struct, [52](#)
- minikappa_ok
 - lspmac.c, [213](#)
 - pgpmac.h, [347](#)
- mk_pgpmac_redis, [11](#)
 - active_simulation, [12](#)
 - asis, [12](#)
 - b, [12](#)
 - bi_list, [12](#)
 - f, [12](#)
 - fnc, [12](#)
 - hard_ini, [12](#)
 - hard_ini_fields, [13](#)
 - head, [13](#)
 - hi, [13](#)
 - i, [13](#)
 - motor_dict, [13](#)
 - motor_field_lists, [13](#)
 - motor_presets, [13](#)
 - p, [13](#)
 - pi, [13](#)
 - ppos, [13](#)
 - pref_ini, [14](#)
 - v, [14](#)
 - x, [14](#)
 - xlate, [14](#)
 - y, [14](#)
 - zoom_settings, [14](#)
- mk_pgpmac_redis.py, [280](#)
- motion_seen
 - lspmac_motor_struct, [52](#)
- motor_dict

- mk_pgpmac_redis, 13
- motor_field_lists
 - mk_pgpmac_redis, 13
- motor_num
 - lspmac_motor_struct, 53
- motor_presets
 - mk_pgpmac_redis, 13
- motors_ht
 - lspmac.c, 213
- moveAbs
 - lspmac_motor_struct, 53
- movevme
 - lspmac_combined_move_struct, 47
- moving_flags
 - md2StatusStruct, 68
- mutex
 - lspg_demandairrights_struct, 21
 - lspg_getcenter_struct, 23
 - lspg_getcurrentsampleid_struct, 25
 - lspg_lock_detector_struct, 26
 - lspg_lock_diffractionmeter_struct, 26
 - lspg_nextsample_struct, 27
 - lspg_nextshot_struct, 37
 - lspg_seq_run_prep_struct, 39
 - lspg_starttransfer_struct, 40
 - lspg_wait_for_detector_struct, 41
 - lspg_waitcryo_struct, 42
 - lspmac_bi_struct, 45
 - lspmac_motor_struct, 53
 - lsredis_obj_struct, 58
- name
 - lspmac_motor_struct, 53
 - lsredis_preset_list_struct, 59
- ncalls
 - lstimer_list_struct, 61
- ncurses_mutex
 - pgpmac.c, 285
 - pgpmac.h, 347
- neg_limit_hit
 - lspmac_motor_struct, 53
- neutral_pos
 - lspmac_motor_struct, 53
- new_timer
 - lstimer.c, 246
- new_value_ready
 - lspg_demandairrights_struct, 21
 - lspg_getcenter_struct, 24
 - lspg_getcurrentsampleid_struct, 25
 - lspg_lock_detector_struct, 26
 - lspg_lock_diffractionmeter_struct, 26
 - lspg_nextsample_struct, 27
 - lspg_nextshot_struct, 37
 - lspg_seq_run_prep_struct, 39
 - lspg_starttransfer_struct, 40
 - lspg_wait_for_detector_struct, 41
 - lspg_waitcryo_struct, 42
- next
 - lsevents_callbacks_struct, 18
 - lsevents_event_names_struct, 18
 - lsevents_listener_struct, 19
 - lsredis_obj_struct, 58
 - lsredis_preset_list_struct, 59
- next_nsecs
 - lstimer_list_struct, 61
- next_secs
 - lstimer_list_struct, 61
- nextsample
 - lspg_nextsample_struct, 27
- nextsample_isnull
 - lspg_nextsample_struct, 28
- nlut
 - lspmac_motor_struct, 53
- no_reply
 - lspmac_cmd_queue_struct, 46
- no_rows_returned
 - lspg_getcenter_struct, 24
 - lspg_getcurrentsampleid_struct, 25
 - lspg_nextsample_struct, 28
 - lspg_nextshot_struct, 37
 - lspg_starttransfer_struct, 40
- not_done
 - lspmac_motor_struct, 53
- now
 - lspg.c, 129
 - lspmac.c, 213
- number_passes
 - md2StatusStruct, 68
- omega
 - lspmac.c, 214
 - pgpmac.h, 347
- omega_act_pos
 - md2StatusStruct, 68
- omega_status_1
 - md2StatusStruct, 68
- omega_status_2
 - md2StatusStruct, 69
- omega_zero_search
 - lspmac.c, 214
- omega_zero_time
 - lspmac.c, 214
 - pgpmac.h, 347
- omega_zero_velocity
 - lspmac.c, 214
- onResponse
 - lspgQueryQueueStruct, 43
 - lspmac_cmd_queue_struct, 46
- options
 - iniParser::iniParser, 16
- p
 - mk_pgpmac_redis, 13
- PMAC_MIN_CMD_TIME
 - lspmac.c, 141
- PMACPORT
 - lspmac.c, 141
- pcmd

- lspmac_cmd_queue_struct, 46
- pgpmac.c, 281
 - main, 282
 - ncurses_mutex, 285
 - pgpmac_printf, 284
 - running, 285
 - stdinService, 284
 - stdinfda, 285
 - term_input, 285
 - term_output, 286
 - term_status, 286
 - term_status2, 286
- pgpmac.h, 286
 - _GNU_SOURCE, 294
 - _lsredis_get_obj, 296
 - alignx, 341
 - aligny, 341
 - alignz, 341
 - anal, 341
 - apery, 341
 - aperz, 341
 - arm_parked, 341
 - blight, 342
 - blight_down, 342
 - blight_f, 342
 - blight_ud, 342
 - blight_up, 342
 - capy, 342
 - capz, 342
 - cenx, 342
 - ceny, 342
 - cryo, 343
 - cryo_back, 343
 - cryo_switch, 343
 - dryer, 343
 - etel_init_ok, 343
 - etel_on, 343
 - etel_ready, 343
 - flight, 343
 - flight_f, 343
 - flight_oo, 344
 - fluo, 344
 - fluor_back, 344
 - fscint, 344
 - fshut, 344
 - hp_air, 344
 - kappa, 344
 - LSPMAC_MAGIC_NUMBER, 294
 - lp_air, 344
 - lsevents_add_listener, 297
 - lsevents_init, 298
 - lsevents_preregister_event, 298
 - lsevents_remove_listener, 298
 - lsevents_run, 299
 - lsevents_send_event, 300
 - lslogging_init, 300
 - lslogging_log_message, 300
 - lslogging_run, 301
 - lspg_array2ptrs, 301
 - lspg_demandairrights, 344
 - lspg_demandairrights_all, 303
 - lspg_demandairrights_t, 295
 - lspg_getcenter, 345
 - lspg_getcenter_call, 303
 - lspg_getcenter_done, 303
 - lspg_getcenter_t, 295
 - lspg_getcenter_wait, 303
 - lspg_getcurrentsampleid, 345
 - lspg_getcurrentsampleid_t, 295
 - lspg_getcurrentsampleid_wait_for_id, 303
 - lspg_init, 304
 - lspg_nextsample, 345
 - lspg_nextsample_all, 304
 - lspg_nextsample_t, 295
 - lspg_nextshot, 345
 - lspg_nextshot_call, 304
 - lspg_nextshot_done, 305
 - lspg_nextshot_t, 295
 - lspg_nextshot_wait, 305
 - lspg_query_push, 305
 - lspg_query_queue_t, 295
 - lspg_run, 306
 - lspg_seq_run_prep_all, 306
 - lspg_starttransfer, 345
 - lspg_starttransfer_call, 306
 - lspg_starttransfer_done, 307
 - lspg_starttransfer_t, 295
 - lspg_starttransfer_wait, 307
 - lspg_waitcryo, 345
 - lspg_waitcryo_all, 307
 - lspg_waitcryo_cb, 307
 - lspg_waitcryo_t, 295
 - lspg_zoom_lut_call, 307
 - lspmac_SockSendDPControlChar, 328
 - lspmac_SockSendDPLine, 328
 - lspmac_SockSendline, 329
 - lspmac_abort, 308
 - lspmac_bi_t, 295
 - lspmac_est_move_time, 308
 - lspmac_est_move_time_wait, 313
 - lspmac_find_motor_by_name, 314
 - lspmac_getBIPosition, 314
 - lspmac_getPosition, 314
 - lspmac_home1_queue, 314
 - lspmac_home2_queue, 316
 - lspmac_init, 316
 - lspmac_jogabs_queue, 320
 - lspmac_motor_t, 295
 - lspmac_motors, 345
 - lspmac_move_or_jog_abs_queue, 320
 - lspmac_move_or_jog_preset_queue, 323
 - lspmac_move_or_jog_queue, 323
 - lspmac_move_preset_queue, 324
 - lspmac_moveabs_queue, 324
 - lspmac_moveabs_wait, 324
 - lspmac_moving_cond, 345

- lspmac_moving_flags, 345
- lspmac_moving_mutex, 346
- lspmac_nmotors, 346
- lspmac_run, 325
- lspmac_set_motion_flags, 327
- lspmac_shutter_cond, 346
- lspmac_shutter_has_opened, 346
- lspmac_shutter_mutex, 346
- lspmac_shutter_state, 346
- lspmac_video_rotate, 329
- lsredis_cmpnstr, 330
- lsredis_cmpstr, 330
- lsredis_cond, 346
- lsredis_find_preset, 330
- lsredis_find_preset_index_by_position, 331
- lsredis_get_obj, 331
- lsredis_get_string_array, 332
- lsredis_getb, 332
- lsredis_getc, 332
- lsredis_getd, 332
- lsredis_getl, 332
- lsredis_getstr, 333
- lsredis_init, 333
- lsredis_load_presets, 334
- lsredis_mutex, 346
- lsredis_obj_t, 295
- lsredis_regexec, 335
- lsredis_run, 336
- lsredis_running, 346
- lsredis_set_preset, 336
- lsredis_setstr, 336
- lctest_main, 337
- lster_timer_init, 337
- lster_timer_run, 338
- lster_timer_set_timer, 338
- lster_timer_unset_timer, 339
- lsupdate_init, 339
- lsupdate_run, 339
- MD2CMDS_CMD_LENGTH, 295
- md2_status_mutex, 346
- md2cmds_cmd, 347
- md2cmds_cond, 347
- md2cmds_init, 339
- md2cmds_md_status_code, 347
- md2cmds_mutex, 347
- md2cmds_pg_cond, 347
- md2cmds_pg_mutex, 347
- md2cmds_run, 340
- minikappa_ok, 347
- ncurses_mutex, 347
- omega, 347
- omega_zero_time, 347
- pgpmac_printf, 340
- phi, 347
- pmac_cmd_queue_t, 296
- pmac_cmd_t, 296
- pmac_queue_cond, 348
- pmac_queue_mutex, 348
- pmac_thread, 215
- PmacSockSendline, 341
- sample_detected, 348
- scint, 348
- shutter_open, 348
- smart_mag_err, 348
- smart_mag_off, 348
- smart_mag_on, 348
- smart_mag_oo, 348
- term_input, 349
- term_output, 349
- term_status, 349
- term_status2, 349
- zoom, 349
- pgpmac_printf
 - pgpmac.c, 284
 - pgpmac.h, 340
- phi
 - lspmac.c, 214
 - pgpmac.h, 347
- phi_act_pos
 - md2StatusStruct, 69
- phi_status_1
 - md2StatusStruct, 69
- phi_status_2
 - md2StatusStruct, 69
- phiscan
 - md2StatusStruct, 69
- pi
 - mk_pgpmac_redis, 13
- pl
 - lspmac_dpascii_queue_struct, 48
- pmac_cmd_queue_t
 - pgpmac.h, 296
- pmac_cmd_size
 - lspmac.c, 141
- pmac_cmd_t
 - pgpmac.h, 296
- pmac_error_strs
 - lspmac.c, 214
- pmac_queue_cond
 - lspmac.c, 215
 - pgpmac.h, 348
- pmac_queue_mutex
 - lspmac.c, 215
 - pgpmac.h, 348
- pmac_thread
 - lspmac.c, 215
- PmacSockSendline
 - pgpmac.h, 341
- pmacfd
 - lspmac.c, 215
- pos_limit_hit
 - lspmac_motor_struct, 53
- position
 - lspmac_bi_struct, 45
 - lspmac_motor_struct, 54
 - lsredis_preset_list_struct, 59
- ppos

- mk_pgpmac_redis, 13
- pq
 - lspmac_motor_struct, 54
- precision
 - lspmac_motor_struct, 54
- pref_ini
 - mk_pgpmac_redis, 14
- previous
 - lspmac_bi_struct, 45
- printf_fmt
 - lspmac_motor_struct, 54
- ptr
 - lspmac_bi_struct, 45
- q
 - lspg.c, 129
- qs
 - lspgQueryQueueStruct, 43
- raw_regexp
 - lsevents_listener_struct, 19
- re
 - lsevents_listener_struct, 19
- read
 - iniParser::iniParser, 16
 - lspmac_motor_struct, 54
- read_mask
 - lspmac_motor_struct, 54
- read_ptr
 - lspmac_motor_struct, 54
- redis_fmt
 - lspmac_motor_struct, 54
- redis_position
 - lspmac_motor_struct, 54
- redisDisconnectCB
 - lsredis.c, 236
- reported_pg_position
 - lspmac_motor_struct, 55
- reported_position
 - lspmac_motor_struct, 55
- Request
 - tagEthernetCmd, 70
- RequestType
 - tagEthernetCmd, 70
- requested_pos_cnts
 - lspmac_motor_struct, 55
- requested_position
 - lspmac_motor_struct, 55
- response_buf
 - lspmac_ascii_buffers_struct, 44
- response_n
 - lspmac_ascii_buffers_struct, 44
- response_str
 - lspmac_ascii_buffers_struct, 44
- roac
 - lsredis.c, 237
- rofd
 - lsredis.c, 238
- rotating
 - md2cmds.c, 280
- rr_cmd
 - lspmac.c, 215
- running
 - pgpmac.c, 285
- sample_detected
 - lspmac.c, 215
 - pgpmac.h, 348
- scint
 - lspmac.c, 215
 - pgpmac.h, 348
- scint_act_pos
 - md2StatusStruct, 69
- scint_piezo
 - md2StatusStruct, 69
- scint_status_1
 - md2StatusStruct, 69
- scint_status_2
 - md2StatusStruct, 69
- sd
 - iniParser::iniParser, 17
- sections
 - iniParser::iniParser, 17
- service_timers
 - lstimer.c, 245
- sfn
 - lspg_nextshot_struct, 37
- sfn_isnull
 - lspg_nextshot_struct, 37
- shots
 - lstimer_list_struct, 61
- shutter_open
 - lspmac.c, 215
 - pgpmac.h, 348
- sindex
 - lspg_nextshot_struct, 37
- sindex2
 - lspg_nextshot_struct, 37
- sindex2_isnull
 - lspg_nextshot_struct, 38
- sindex_isnull
 - lspg_nextshot_struct, 38
- skey
 - lspg_nextshot_struct, 38
- skey_isnull
 - lspg_nextshot_struct, 38
- smart_mag_err
 - lspmac.c, 215
 - pgpmac.h, 348
- smart_mag_off
 - lspmac.c, 215
 - pgpmac.h, 348
- smart_mag_on
 - lspmac.c, 216
 - pgpmac.h, 348
- smart_mag_oo
 - lspmac.c, 216
 - pgpmac.h, 348

- sstart
 - lspg_nextshot_struct, 38
- sstart2
 - lspg_nextshot_struct, 38
- sstart2_isnull
 - lspg_nextshot_struct, 38
- sstart_isnull
 - lspg_nextshot_struct, 38
- starttransfer
 - lspg_starttransfer_struct, 40
- status1
 - lspmac_motor_struct, 55
- status1_p
 - lspmac_motor_struct, 55
- status2
 - lspmac_motor_struct, 55
- status2_p
 - lspmac_motor_struct, 55
- status_str
 - lspmac_motor_struct, 55
- stdinService
 - pgpmac.c, 284
- stdinfa
 - pgpmac.c, 285
- stype
 - lspg_nextshot_struct, 38
- stype2
 - lspg_nextshot_struct, 38
- stype2_isnull
 - lspg_nextshot_struct, 39
- stype_isnull
 - lspg_nextshot_struct, 39
- subac
 - lsredis.c, 238
- subfd
 - lsredis.c, 238
- tagEthernetCmd, 70
 - bData, 70
 - Request, 70
 - RequestType, 70
 - wIndex, 71
 - wLength, 71
 - wValue, 71
- term_input
 - pgpmac.c, 285
 - pgpmac.h, 349
- term_output
 - pgpmac.c, 286
 - pgpmac.h, 349
- term_status
 - pgpmac.c, 286
 - pgpmac.h, 349
- term_status2
 - pgpmac.c, 286
 - pgpmac.h, 349
- time_sent
 - lspmac_cmd_queue_struct, 46
- u2c
 - lspmac_motor_struct, 56
- unit
 - lspmac_motor_struct, 56
- update_resolution
 - lspmac_motor_struct, 56
- v
 - md2cmds_cmd_kv_struct, 62
 - mk_pgpmac_redis, 14
- VR_CTRL_RESPONSE
 - lspmac.c, 141
- VR_DOWNLOAD
 - lspmac.c, 141
- VR_FWDOWNLOAD
 - lspmac.c, 141
- VR_IPADDRESS
 - lspmac.c, 141
- VR_PMAC_FLUSH
 - lspmac.c, 141
- VR_PMAC_GETBUFFER
 - lspmac.c, 141
- VR_PMAC_GETLINE
 - lspmac.c, 141
- VR_PMAC_GETMEM
 - lspmac.c, 141
- VR_PMAC_GETRESPONSE
 - lspmac.c, 142
- VR_PMAC_PORT
 - lspmac.c, 142
- VR_PMAC_READREADY
 - lspmac.c, 142
- VR_PMAC_SENDCTRLCHAR
 - lspmac.c, 142
- VR_PMAC_SENDLINE
 - lspmac.c, 142
- VR_PMAC_SETBIT
 - lspmac.c, 142
- VR_PMAC_SETBITS
 - lspmac.c, 142
- VR_PMAC_SETMEM
 - lspmac.c, 142
- VR_PMAC_WRITEBUFFER
 - lspmac.c, 142
- VR_PMAC_WRITEERROR
 - lspmac.c, 142
- VR_UPLOAD
 - lspmac.c, 142
- valid
 - lsredis_obj_struct, 58
- value
 - lsredis_obj_struct, 58
- value_length
 - lsredis_obj_struct, 58
- wIndex
 - tagEthernetCmd, 71
- wLength
 - tagEthernetCmd, 71

- wValue
 - tagEthernetCmd, [71](#)
- wait_for_me
 - lsredis_obj_struct, [59](#)
- win
 - lspmac_motor_struct, [56](#)
- wrac
 - lsredis.c, [238](#)
- wrfd
 - lsredis.c, [238](#)
- write_fmt
 - lspmac_motor_struct, [56](#)
- x
 - mk_pgpmac_redis, [14](#)
- xlake
 - mk_pgpmac_redis, [14](#)
- y
 - mk_pgpmac_redis, [14](#)
- zoom
 - lspg_getcenter_struct, [24](#)
 - lspmac.c, [216](#)
 - pgpmac.h, [349](#)
- zoom_act_pos
 - md2StatusStruct, [69](#)
- zoom_isnull
 - lspg_getcenter_struct, [24](#)
- zoom_settings
 - mk_pgpmac_redis, [14](#)
- zoom_status_1
 - md2StatusStruct, [69](#)
- zoom_status_2
 - md2StatusStruct, [69](#)