**Commands to Control the 1-DOF Laser Robot**

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| **Command** | Shorthand | Parameter | Description |
| todeg | td | float (degrees) | Rotate to an absolute degree position. |
| bydeg | bd | float (degrees) | Rotate by a specified degree. |
| tostep | ts | int (steps) | Rotate to an absolute step position. |
| bystep | bs | int (steps) | Rotate by a specified number of steps. |
| tohole | th | int (hole number) | Rotate to an absolute hole position. |
| byhole | bh | int (hole number) | Rotate by a specified number of holes. |
| setdeg | sd | float (degrees) | Set the current position in degrees. |
| setstep | ss | int (steps) | Set the current position in steps. |
| settlr | st | int (microseconds) | Set the delay tolerance in microseconds. |
| setzero | sz | No parameter | Set the current position to zero degrees. |
| homezero | hz | No parameter | Home to the zero position. |
| tolimsw | tl | No parameter | Rotate to the limit switch. |
| laseron | ln | No parameter | Turn on the laser. |
| laseroff | lf | No parameter | Turn off the laser. |
| beam | bm | int (duration in ms) | Emit a laser beam for a specified duration. |
| withweight | ww | No parameter | Set the position of limit switch for use with weight. |
| noweight | nw | No parameter | Set the position of limit switch for use without weight. |
| printpos | pp | No parameter | Print the current position in steps and degrees. |

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