

SM151E Software Manual

Windows GCS 2.0 DLL (PI_GCS2_DLL)

Release: 2.10.1 Date: 2019-08-27

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Document Number SM151E, BRo, Release 2.10.1

PIGCS_2_0_DLL_SM151E.doc

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1. Introduction

The PI GCS2_library allows controlling one or more PI controllers connected to a host PC. The PI General Command Set (GCS) is the PI standard command set and ensures the compatibility between different PI controllers.

The library is available for the following operating systems:

- **Windows** Windows 7 (32 bit, 64 bit), Windows 8 (32 bit, 64 bit) and Windows 10 (32 bit, 64 bit): PI GCS2 DLL
See Section 3.2 starting on p. 6 for more information about PI DLLs.
- **Linux** operating systems (kernel 2.6, GTK 2.0, glibc 2.15): libpi_pi_gcs2.so.x.x.x and libpi_pi_gcs2-x.x.x.a where x.x.x gives the version of the library

NOTES

This manual was originally written for the Windows version of the GCS library (DLL), and so the terminology used in this document is that common with Windows DLLs. Nevertheless this manual can also be used for the Linux versions of the GCS library because there is no difference in the functionality of the library functions between the individual operating systems.

See Section 3 starting on p. 6 for more information about PI DLLs.

There are various sample programs for different programming languages to be found in the \Sample directory of the CD of your controller.

2. Software Installation

To install the PI GCS 2 DLL on your host PC, follow the installation instructions for the PC software in the user manual of the controller.

With Windows operating systems:

You can also install the feature “PI_Programming_Files_PI_GCS2_DLL_Setup.exe” located in the “SingleSetups” folder of the product CD. Afterwards, the required files will be located in C:\Users\Public\PI\PI_Programming_Files_PI_GCS2_DLL.

The following files are installed:

PI_GCS2.cs	C# class calling methods of PI_GCS2_DLL. Can be used in any .NET project to call the PI_GCS2_DLL. This is used in the C# and VB.NET samples on the product CD
PI_GCS2_DLL.bas	Visual Basic 6 module calling the methods of the PI_GCS2_DLL
PI_GCS2_DLL.dll	The 32-bit version of the dynamic library, this file needs to be available during runtime and is loaded by the operating system
PI_GCS2_DLL.h	C header file with the declarations of all PI_GCS2_DLL methods. Needed for C and C++ projects
PI_GCS2_DLL.lib	Linker file for the 32-bit version, this can be used for statically linking the DLL
PI_GCS2_DLL_PF.h	C header file defining types for function pointers for each method of the PI_GCS2_DLL. This is helpful when loading the DLL dynamically during runtime (see “Using System Functions to Load Library” on p. 7.
PI_GCS2_DLL_x64.dll	The 64-bit version of the dynamic library, this file needs to be available during runtime and is loaded by the operating system
PI_GCS2_DLL_x64.lib	Linker file for the 64-bit version, this can be used for statically linking the DLL

There is also a folder “noGUI” with special versions of the PI_GCS2_DLL without the code for the graphical user interface – i.e., PI_InterfaceSetupDlg() will simply return with no effect. In order to show a dialog window while calling PI_InterfaceSetupDlg() the PI_GCS2_DLL needs to call some “native” windows methods to initialize the graphical user interfaces. Sometimes the runtime of the custom application does not allow this and the PI_GCS2_DLL cannot be loaded. In these cases the “noGUI” versions can solve this issue. The following files are in the “noGUI” folder:

noGUI\PI_GCS2_DLL.dll	The 32-bit version of the dynamic library without code for the graphical user interface, this file needs to be available during runtime and is loaded by the operating system
noGUI\PI_GCS2_DLL.lib	Linker file for the 32-bit version without code for the graphical user interface, this can be used for statically linking the DLL
noGUI\PI_GCS2_DLL_x64.dll	The 64-bit version of the dynamic library without code for the graphical user interface, this file needs to be available during runtime and is loaded by the operating system
noGUI\PI_GCS2_DLL_x64.lib	Linker file for the 64-bit version without code for the graphical user interface, this can be used for statically linking the DLL

Copy these files to the location where the source code of your application is built (.h. and .lib) and where the application is executed (.dll).

With some controllers, you can select a parameter set appropriate for your positioner from a positioner database, see “Functions for Positioner Databases” (p. 130).

NOTE

Positioner database files are installed in the ...\\PI\\GcsTranslator directory.

The location of the PI directory is that specified upon installation, usually in C:\\ProgramData. If this directory does not exist, the EXE file that needs the positioner databases will look in its own directory. Note that in PIMikroMove, you can use the *Version Info* item in the controller menu or the *Search for controller software* item in the *Connections* menu to identify the GCSTranslator path.

PI is constantly improving the PC software. Always install the latest version of the PC software and the standard positioner databases. Follow the update instructions for the PC software in the user manual of the controller. With Windows operating systems, use the PI Update Finder.

3. General Information About PI DLLs

The information below is valid for the DLL described in this manual as well as for the DLLs for many other PI products.

3.1. Threads

This DLL is not thread-safe. The function calls of the DLL are not synchronized and can be safely used only by one thread at a time.

3.2. DLL Handling

To get access to and use the DLL functions, the library must be included in your software project. There are a number of techniques supported by the Windows operating system and supplied by the different development systems. The following sections describe the methods which are most commonly used. For detailed information, consult the relevant documentation of the development

environment being used. (It is possible to use the PI_GCS2_DLL.DLL in Delphi projects. Please see <http://www.drBob42.com/delphi/headconv.htm> for a detailed description of the steps necessary.)

3.2.1. Using a Static Import Library

The PI_GCS2_DLL.DLL module is accompanied by the PI_GCS2_DLL.LIB file. This is the static import library which can be used by the Microsoft Visual C++ system for 32-bit applications. In addition, other systems, like the National Instruments LabWindows CVI or Watcom C++ can handle, i.e. understand, the binary format of a VC++ static library. When the static library is used, the programmer must:

Use a header or source file in which the DLL functions are declared, as needed for the compiler. The declaration should take into account that these functions come from a "C-Language" Interface. When building a C++ program, the functions have to be declared with the attribute specifying that they are coming from a C environment. The VC++ compiler needs an extern "C" modifier. The declaration must also specify that these functions are to be called like standard Win-API functions. That means the VC++ compiler needs to see a WINAPI or __stdcall modifier in the declaration.

Add the static import library to the program project. This is needed by the linker and tells it that the functions are located in a DLL and that they are to be linked dynamically during program startup.

3.2.2. Using a Module Definition File

The module definition file is a standard element/resource of a 16- or 32-bit Windows application. Most IDEs (integrated development environments) support the use of module definition files. Besides specification of the module type and other parameters like stack size, function imports from DLLs can be declared. In some cases the IDE supports static import libraries. If that is the case, the IDE might not support the ability to declare DLL-imported functions in the module definition file. When a module definition file is used, the programmer must:

Use a header or source file where the DLL functions have to be declared, which is needed for the compiler. In the declaration should be taken into account that these function come from a "C-Language" Interface. When building a C++ program, the functions have to be declared with the attribute that they are coming from a C environment. The VC++ compiler needs an extern "C" modifier. The declaration also must be aware that these functions have to be called like standard Win-API functions. Therefore the VC++ compiler needs a WINAPI or __stdcall modifier in the declaration.

Modify the module definition file with an IMPORTS section. In this section, all functions used in the program must be named. Follow the syntax of the IMPORTS statement. Example:

```
IMPORTS
  PI_GCS2_DLL.PI_IsConnected
```

3.2.3. Using System Functions to Load Library

If the library is not to be loaded during program startup, it can sometimes be loaded during program execution using functions of the operating system. The entry point for each desired function has to be obtained. The DLL linking/loading with system functions during program execution can always be done, independent of the development system or files which have to be added to the project. When the DLL/shared library is loaded dynamically during program execution, the programmer has to:

Use a header or source file in which local or global pointers of a type appropriate for pointing to a function entry point are defined. This type could be defined in a typedef expression. In the following example, the type FP_PI_IsConnected is defined as a pointer to a function which has an int as argument and returns a BOOL value. Afterwards a variable of that type is defined. The PI_GCS2_DLL_PF.h file provides these types for the methods of PI_GCS2_DLL.

```
typedef BOOL (WINAPI *FP_PI_IsConnected)( int );
FP_PI_IsConnected pPI_IsConnected;
```

Call LoadLibrary() for WIN32 API or dlopen () on Linux. The library must be loaded into the process address space of the application before access to the library functions is possible. This is why one of these functions has to be called. The instance handle obtained has to be saved for later use.

Call -GetProcAddress() for the Win32 API or dlsym () for Linux for each desired DLL function. To call a library function, the entry point in the loaded module must be known. This address can be assigned to the appropriate function pointer using one of these functions. Afterwards the pointer can be used to call the function.

Examples:

Load DLL using Win32 API:

```
#include <windows.h>
#include <stdio.h>

#include "PI_GCS2_DLL_PF.h"

int main(int argc, char* argv[])
{
    HMODULE hPI_Dll = LoadLibrary ("PI_GCS2_DLL.DLL");
    printf("Handle:  %d\n", int (hPI_Dll) );

    int ID = -1;

    PFPI_ConnectRS232 PI_ConnectRS232;
    PI_ConnectRS232 =
        (PFPI_ConnectRS232) GetProcAddress(hPI_Dll, "PI_ConnectRS232");

    PFPI_MOV PI_MOV;
    PI_MOV = (PFPI_MOV) GetProcAddress (hPI_Dll, "PI_MOV");

    ID = PI_ConnectRS232 (1, 115200);
    printf("ID: %d\n", ID);

    double l_dPos = 15.0;
    PI_MOV(ID, "1",  &l_dPos);

    Sleep(1000);

    l_dPos = 25.0;
    PI_MOV(ID, "1",  &l_dPos);

    return 0;
}
```


Load DLL using Linux API:

```
#include <string.h>
#include <unistd.h>

#include <stdlib.h>
#include <stdio.h>
#include <dlfcn.h>

#include "PI_GCS2_DLL_PF.h"

int main (int argc, char* argv[])
{
    void* hPI_Dll = dlopen ("libpi_pi_gcs2.so", RTLD_NOW);
    printf("Handle:  %d\n",hPI_Dll);

    int ID = -1;

    PFPI_ConnectRS232ByDevName PI_ConnectRS232ByDevName;
    PI_ConnectRS232ByDevName =
        (PFPI_ConnectRS232ByDevName) dlsym (hPI_Dll, "PI_ConnectRS232ByDevName");

    PFPI_MOV PI_MOV;
    PI_MOV = (PFPI_MOV) dlsym (hPI_Dll, "PI_MOV");

    ID = PI_ConnectRS232ByDevName ("/dev/ttyS1", 115200);
    printf ("ID: %d\n", ID);

    double l_dPos = 15.0;
    PI_MOV (ID,"1", &l_dPos);

    sleep (1);

    l_dPos = 25.0;
    PI_MOV (ID,"1", &l_dPos);

    return 0;
}
```

3.3. Function Calls

The first argument to most function calls is the ID of the selected controller.

3.3.1. Error Return

Almost all functions will return a boolean value of type **BOOL** (see “Boolean Values” (p. 10)). The result will be zero if the DLL finds errors in the command or cannot transmit it successfully, or if the DLL internal error status is non-zero for another reason. If the command is acceptable and transmission is successful, and if the library has controller error checking enabled (see **PI_SetErrorCheck()**), the return value will further reflect the error status of the controller immediately after the command was sent. **TRUE** indicates no error. To find out what went wrong when the call returns **FALSE**, call **PI_GetError()** to obtain the error code, and, if desired, translate it to the corresponding error message with **PI_TranslateError()**. The error codes and messages are listed in “Error Codes” (p. 136).

3.3.2. Axis Identifiers

Many commands accept one or more axis identifiers. If no axes are specified (either by giving an empty string or a **NULL** pointer) some commands will address all connected axes. Axes names are separated by a space “ ”.

3.3.3. Axis Parameters

Parameters for specified axes are stored in an array passed to the function. The parameter for the first axis is stored in array[0], for the second axis in array[1], and so on. So, if you call **PI_qPOS("1 2 n3", double pos[3])**, the position for '1' is in pos[0], for '2' in pos[1] and for '3' in pos[2]. If you call **PI_MOV("1 3", double pos[2])** the target position for '1' is in pos[0] and for '3' in pos[1].

If conflicting specifications are present, only the **last** occurrence is actually sent to the controller with its argument(s). Thus, if you call **PI_MOV("1 1 2", pos[3])** with pos[3] = { 1.0, 2.0, 3.0 }, '1' will move to 2.0 and '2' to 3.0. If you then call **PI_qPOS("1 1 2", pos[3])**, pos[0] and pos[1] will contain 2.0 as the position of '1'.

3.4. Types Used in PI Software

3.4.1. Boolean Values

The library uses the convention used in Microsoft's C++ for boolean values. If your compiler does not support this directly, it can be easily set up: Just add the following lines to a central header file of your project:

```
typedef int BOOL;
#define TRUE 1
#define FALSE 0
```

3.4.2. NULL Pointers

In the library and the documentation "null pointers" (pointers pointing nowhere) have the value **NULL**. This is defined in the windows environment. If your compiler does not know this, simply use:

```
#define NULL 0
```

3.4.3. C-Strings

The library uses the C convention to handle strings. Strings are stored as char arrays with '\0' as terminating delimiter. Thus, the "type" of a c-string is char*. Do not forget to provide enough memory for the final '\0'. If you declare:

```
char* text = "HELLO";
```

it will occupy 6 bytes in memory. To remind you of the zero at the end, the names of the corresponding variables start with "sz".

4. Communication Functions

4.1. Usage and Overview

To use the DLL and communicate with the controller, the DLL must be initialized with one of the "connect" functions:

- `PI_InterfaceSetupDlg()`
- `PI_ConnectNIgpib()`
- `PI_ConnectRS232()`
- `PI_ConnectDaisyChainDevice()`
- `PI_ConnectTCPIP()`
- `PI_ConnectTCPIPbyDescription()`
- `PI_ConnectUSB()`
- `PI_ConnectUSBWithBaudRate()`.

To allow the handling of multiple controllers, the open functions return a non-negative ID. This is a kind of index to an internal array storing the information for the (different) controllers. All other calls addressing the same controller have this ID as their first parameter. `PI_CloseConnection()` (p.35) will close the connection to the specified controller and free its system resources.

Daisy Chain

Note that before connecting a daisy chain device using the `PI_ConnectDaisyChainDevice()` function, the daisy chain port has to be opened using the `PI_OpenRS232DaisyChain()` or the `PI_OpenUSBdaisyChain` function, whichever is the appropriate one.

After the daisy chain port has been opened all controllers connected to this daisy chain port can be "opened" using `PI_ConnectDaisyChainDevice()`. A connection to a daisy chain device is closed using the `PI_CloseConnection()` function. To close the daisy chain port the `PI_CloseDaisyChain()` function has to be called.

For controllers whose address can be set with DIP switches: In a daisy-chain, connected via USB or via RS-232, there must be one controller with address 1. It is not required that this controller is directly connected to the host PC, i.e. this controller does not have to be the first controller of the daisy-chain. If there is no controller in a daisy-chain with address 1 an error message occurs when you try to setup a connection. All controllers in a daisy chain must be set to the same baud rate.

TCP/IP

Before connecting a device using the `PI_ConnectTCPIPbyDescription()` function, its description string should be queried by `PI_EnumerateTCPIPDevices()`.

USB

Before connecting a device using the `PI_ConnectUSB()` function, its description string should be queried by `PI_EnumerateUSB()`.

USB and Virtual COM Ports

The USB driver for some PI devices consists of two layers: The basic USB layer and a virtual COM port. The COM port is offered for convenience. There are legacy applications which can communicate with RS-232 to additional hardware (e.g. microscopy application where you can store command sequences that can be sent over RS-232). These applications can use the PI device with Windows's built in RS-232 support using the virtual COM port – even if the hardware connection is USB.

If you have more than one device connected to the PC, the COM port assignment is randomly chosen by the operating system. E.g. on one PC two devices may be available as COM3 and COM4, while they may be available as COM4 and COM7 on a another PC.

If you use the USB driver directly (i.e. the basic USB layer) you can connect to the device using its serial number.

The PI_GCS2_DLL supports both ways: Use either PI_ConnectRS232() with the number of the virtual COM port (baud rate doesn't matter, use 115200), or use PI_ConnectUSB() with the serial number of the device. You can also call PI_EnumerateUSB () to get a list of all connected PI devices and select the device from the list.

List of Communications Functions

Function	Short Description	Page
BOOL PI_CancelConnect (int threadId)	Cancel connecting thread with given ID	13
void PI_CloseConnection (int ID)	Close connection to the controller	13
void PI_CloseDaisyChain (int iPortId)	Close connection to the daisy chain port	13
int PI_ConnectDaisyChainDevice (int iPortId, int iDeviceNumber)	Open a daisy chain device	14
int PI_ConnectNIgpiB (int iChannelNr, int iDeviceAddress)	Open a connection from a National Instruments IEEE 488 board to the controller	14
int PI_ConnectRS232 (int iPortNumber, int iBaudRate)	Open an RS-232 ("COM") interface to a controller	14
int PI_ConnectRS232ByDevName (const char* szDevName, int BaudRate)	Open an RS-232 interface to a controller for Linux	14
int PI_ConnectTCPIP (const char* szHostname, int port)	Open a TCP/IP connection to the controller	14
int PI_ConnectTCPIPbyDescription (const char* szDescription)	Open a TCP/IP connection to the controller using one of the identification strings listed by PI_EnumerateTCPIPDevices()	15
int PI_ConnectUSB (const char* szDescription)	Open an USB connection to a controller using one of the identification strings listed by PI_EnumerateUSB()	15
int PI_ConnectUSBWithBaudRate (const char* szDescription, int iBaudRate)	Open an USB connection to a controller using one of the identification strings listed by PI_EnumerateUSB()	15
void PI_EnableBaudRateScan (BOOL enableBaudRateScan)	Switches off the internal baudrate scan of the PI_ConnectUSB() and PI_ConnectRS232() functions	15
int PI_EnableTCPIPScan (int iMask)	Selects the network hardware type (e.g. Lantronix XPort or other Ethernet device) which is to be found by PI_EnumerateTCPIPDevices()	15
int PI_EnumerateTCPIPDevices (char* szBuffer, int iBufferSize, const char* szFilter)	Lists the identification strings of all controllers available in the network via TCP/IP	16
int PI_EnumerateUSB (char* szBuffer, int iBufferSize, const char* szFilter)	Lists the identification strings of all controllers available via USB interfaces	16
int PI_GetControllerID (int threadID)	Get ID of connected controller for given threadID	16
int PI_GetError (int ID)	Get error status of the DLL and, if clear, that of the controller	16

Function	Short Description	Page
int PI_InterfaceSetupDlg (const char* szRegKeyName)	Open dialog to let user select the interface and create a new PI object	16
BOOL PI_IsConnected (int ID)	Check if there is a controller with an ID of <i>ID</i>	17
BOOL PI_IsConnecting (int threadID, BOOL* bConnecting)	Check if thread with given ID is running trying to establish communication	17
int PI_OpenRS232DaisyChain (int iPortNumber, int iBaudRate, int* piNumberOfConnectedDaisyChainDevices, char* szDeviceIDNs, int iBufferSize)	Open a RS-232 ("COM") interface to a daisy chain and set the baud rate of the daisy chain master	17
int PI_OpenUSBdaisyChain (const char* szDescription, int* piNumberOfConnectedDaisyChainDevices, char* szDeviceIDNs, int iBufferSize)	Open a USB interface to a daisy chain	17
void PI_SetConnectTimeout (int timeoutInMS)	Changes the internal timeout of all PI_Connect...() functions	18
BOOL PI_SetErrorCheck (int ID, BOOL bErrorCheck)	Set error-check mode of the library	18
BOOL PI_TranslateError (int iErrorNumber, char* szErrorMessage, int iBufferSize)	Translate error number to error message	18
int PI_TryConnectRS232 (int port, int baudrate)	Starts background thread which tries to establish connection to controller with given RS-232 settings	18
int PI_TryConnectUSB (const char* szDescription)	Starts background thread which tries to establish connection to controller with given USB settings	66

4.2. Function Description

BOOL **PI_CancelConnect** (int *threadID*)

Cancel connecting thread with given thread ID

Arguments:

Thread ID

Returns:

TRUE if thread was cancelled, **FALSE** if no thread with given ID was running

void **PI_CloseConnection** (int *ID*)

Close connection to the controller associated with *ID*. *ID* will not be valid after this call.

Arguments:

ID ID of controller, if *ID* is not valid nothing will happen.

void **PI_CloseDaisyChain** (int *iPortID*)

Close connection to the daisy chain port associated with *iPortID*. *iPortID* will not be valid after this call.

Note that if there are still some open connections to one or more daisy chain devices, these connections will be closed automatically.

Arguments:

iPortID ID of the daisy chain port, if *iPortID* is not valid nothing will happen.

int PI_ConnectDaisyChainDevice (int *iPortId*, int *iDeviceNumber*)

Open a daisy chain device. All future calls to control this device need the ID returned by this call. Note that before connecting a daisy chain device using the PI_ConnectDaisyChainDevice() function, the daisy chain port has to be opened using the PI_OpenRS232DaisyChain() or the PI_OpenUSBDAisyChain() function, whichever is the appropriate one.

After the daisy chain port has been opened all controllers connected to this daisy chain port can be "opened" using PI_ConnectDaisyChainDevice(). A connection to a daisy chain device is closed using the PI_CloseConnection() function. To close the daisy chain port the PI_CloseDaisyChain() function has to be called. Closing the daisy chain port automatically closes all still opened daisy chain devices.

Arguments:

iPortId the ID of the daisy chain port. This ID is returned by PI_OpenRS232DaisyChain().

iDeviceNumber the number of the daisy chain device to use, is a value between 1 and the *piNumberOfConnectedDaisyChainDevices* value of the PI_OpenRS232DaisyChain() function.

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

int PI_ConnectNIgpib (int *iBoard*, const int *iDeviceAddress*)

Open a connection from a National Instruments IEEE 488 board to the controller. All future calls to control this controller need the ID returned by this call.

Arguments:

iBoard number of board (check with NI installation software)

iDeviceAddress address of connected device

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

int PI_ConnectRS232 (int *iPortNumber*, int *iBaudRate*)

Open an RS-232 ("COM") interface to a controller. The call also sets the baud rate on the controller side. All future calls to control this controller need the ID returned by this call.

Arguments:

iPortNumber COM port to use (e.g. 1 for "COM1")

iBaudRate to use

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

int PI_ConnectRS232ByDevName (const char* *szDevName*, int *BaudRate*)

Open an RS-232 interface to a controller with Linux. The call also sets the baud rate on the controller side. All future calls to control this controller need the ID returned by this call.

Arguments:

szDevName device interface name for RS232 connection (Linux)

iBaudRate to use

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

int PI_ConnectTCPIP (const char* *szHostname*, int *port*)

Open a TCP/IP connection to the controller. All future calls to control this controller need the ID returned by this call. Will fail if there is already a connection.

Communication cannot be maintained after the controller is power-cycled or rebooted. The connection must then be closed and reopened.

Arguments:

szHostname host name of the controller, can be the IP address, e.g. "192.168.1.1" (Leading zeros may cause problems)

port port to connect to. For controllers from PI, the port is always 50000.

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding, or controller responds that it is already connected via TCP/IP.

int PI_ConnectTCPIPbyDescription (const char* szDescription)

Open a TCP/IP connection to the controller using one of the identification strings listed by PI_EnumerateTCPIPDevices(). All future calls to control this controller need the ID returned by this call. Will fail if there is already a connection.

Communication cannot be maintained after the controller is power-cycled or rebooted. The connection must then be closed and reopened.

Arguments:

szDescription the description of the controller returned by PI_EnumerateTCPIPDevice

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding, or controller responds that it is already connected via TCP/IP.

int PI_ConnectUSB (const char* szDescription)

Open an USB connection to a controller using one of the identification strings listed by PI_EnumerateUSB(). All future calls to control this controller need the ID returned by this call. Will fail if there is already a connection.

Communication cannot be maintained after the controller is power-cycled or rebooted. The connection must then be closed and reopened.

Arguments:

szDescription the description of the controller returned by PI_EnumerateUSB

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding, or the controller responds that it is already connected via USB.

int PI_ConnectUSBWithBaudRate (const char* szDescription,int iBaudRate)

Open an USB connection to a controller using one of the identification strings listed by PI_EnumerateUSB(). By specifying the baud rate, a connection using a different baudrate than the standard will be established more quickly. All future calls to control this controller need the ID returned by this call. Will fail if there is already a connection.

Communication cannot be maintained after the controller is power-cycled or rebooted. The connection must then be closed and reopened.

Arguments:

szDescription the description of the controller returned by PI_EnumerateUSB

iBaudRate: to use

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding, or the controller responds that it is already connected via USB.

void PI_EnableBaudRateScan (BOOL enableBaudRateScan)

Switches off the internal baudrate scan of the PI_ConnectUSB() and PI_ConnectRS232() functions. By default, the baudrate scan is on. To switch off the baudrate scan, PI_EnableBaudRateScan() has to be called before PI_ConnectUSB() and PI_ConnectRS232().

Arguments:

enableBaudRateScan switch baudrate scan on (TRUE) or off (FALSE).

int PI_EnableTCPIPScan (int iMask)

Selects the network hardware type (e.g. Lantronix XPort or other Ethernet device) which is to be found by PI_EnumerateTCPIPDevices(). By default, all devices will be found—change the settings only in special cases and if you know which Ethernet hardware is implemented in your controller.

Arguments:

iMask Bit mask 1 = UDP; 2 = XPORT

Returns:

The previous bit mask

```
int PI_EnumerateTCPIPDevices (char* szBuffer, int iBufferSize, const char* szFilter)
```

Lists the identification strings of all controllers available in the network via TCP/IP. Using the mask, you can filter the results for certain text.

Arguments:

szBuffer buffer for the TCP/IP devices description.

iBufferSize

szFilter only controllers whose descriptions match the filter are returned in the buffer (e.g. a filter of "E-517" will only return the E-517 controllers, and not all PI controllers).

Returns:

>= 0: the number of controllers in the list

<0: Error code

```
int PI_EnumerateUSB (char* szBuffer, int iBufferSize, const char* szFilter)
```

Lists the identification strings of all controllers available via USB interfaces. Using the mask, you can filter the results for certain text.

Arguments:

szBuffer buffer for the USB devices description.

iBufferSize size of the buffer

szFilter only controllers whose descriptions match the filter are returned in the buffer (e.g. a filter of "E-861" will only return the E-861 controllers, and not all PI controllers).

Returns:

>= 0: the number of controllers in the list

<0: Error code

```
int PI_GetControllerID(int threadID)
```

Get ID of connected controller for given thread ID.

Arguments:

Thread ID

Returns:

ID of new controller (>=0), error code (<0) if there was an error, no thread running, or thread has not finished yet

```
int PI_GetError (int ID)
```

Get error status of the DLL and, if clear, that of the controller. If the library shows an error condition, its code is returned, if not, the controller error code is checked using **PI_qERR()** (p.136) and returned. After this call the DLL internal error state will be cleared; the controller error state will be cleared if it was queried.

Returns:

error ID, see **Error codes** (p. 136) for the meaning of the codes.

```
int PI_InterfaceSetupDlg (const char* szRegKeyName)
```

Open dialog to let user select the interface and create a new PI object. All future calls to control this controller need the ID returned by this call. See **Interface Settings** (p. 19) for a detailed description of the dialogs shown.

Arguments:

szRegKeyName key in the Windows registry in which to store the settings, the key used is "HKEY_LOCAL_MACHINE\SOFTWARE\<your keyname>" if *keyname* is **NULL** or "" the default key "HKEY_LOCAL_MACHINE\SOFTWARE\PI\PI_GCS2_DLL" is used.

Note:

If your programming language is C or C++, use '\\' if you want to create a key and a subkey at once.

To create "MyCompany\PI_GCS2_DLL" you must call

```
PI_InterfaceSetupDlg( "MyCompany\\PI_GCS2_DLL" )
```


Returns:

ID of new object, -1 if user pressed "CANCEL", the interface could not be opened, or no controller is responding.

BOOL PI_IsConnected (int *ID*)

Check if there is a controller with an ID of *ID*.

Returns:

TRUE if *ID* points to an existing controller, **FALSE** otherwise.

BOOL PI_IsConnecting(int *threadID*, BOOL* *bConnecting*)

Check if thread with given ID is running trying to establish communication.

Arguments:

Thread ID

bConnecting **TRUE** if thread is running **FALSE** if no thread is running with given ID

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

int PI_OpenRS232DaisyChain (int *iPortNumber*, int *iBaudRate*, int* *piNumberOfConnectedDaisyChainDevices*, char* *szDeviceIDNs*, int *iBufferSize*)

Open a RS-232 ("COM") interface to a daisy chain and set the baud rate of the daisy chain master. Note that calling this function does not open a daisy chain device—to get access to a daisy chain device you have to call PI_ConnectDaisyChainDevice()! All future calls to PI_ConnectDaisyChain() need the ID returned by PI_OpenRS232DaisyChain(). The *iDeviceNumber* of the PI_ConnectDaisyChain() function is a value between 1 and the *piNumberOfConnectedDaisyChainDevices*.

Arguments:

iPortNumber COM port to use (e.g. 1 for "COM1")

iBaudRate to use

piNumberOfConnectedDaisyChainDevices variable to receive the number of connected daisy chain devices.

szDeviceIDNs buffer to receive the IDN strings of the controllers (see PI_qIDN()).

iBufferSize the size of the buffer *szDeviceIDNs*.

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

int PI_OpenUSBDAISYChain (const char* *szDescription*, long* *piNumberOfConnectedDaisyChainDevices*, char* *szDeviceIDNs*, int *iBufferSize*)

Open a USB interface to a daisy chain. Note that calling this function does not open a daisy chain device—to get access to a daisy chain device you have to call PI_ConnectDaisyChainDevice()! All future calls to PI_ConnectDaisyChain() need the ID returned by PI_OpenUSBDAISYChain(). The *iDeviceNumber* of the PI_ConnectDaisyChain() function is a value between 1 and the *piNumberOfConnectedDaisyChainDevices*.

Arguments:

szDescription the description of the controller returned by PI_EnumerateUSB

piNumberOfConnectedDaisyChainDevices variable to receive the number of connected daisy chain devices.

szDeviceIDNs buffer to receive the IDN strings of the controllers (see PI_qIDN()).

iBufferSize the size of the buffer *szDeviceIDNs*.

Returns:

ID of new object, -1 if interface could not be opened or no controller is responding.

void PI_SetConnectTimeout (int *timeoutInMS*)

Changes the internal timeout of all PI_Connect...() functions. To change the timeout, PI_SetConnectTimeout() has to be called before a PI_Connect...() function.

Arguments:

timeoutInMS is the timeout to be set in milliseconds. By default, the timeout is set to 10,000 ms.

BOOL PI_SetErrorCheck (int *ID*, BOOL *bErrorCheck*)

Set error-check mode of the library. With this call you can specify whether the library should check the error state of the controller (with "ERR?") after sending a command. This will slow down communications, so if you need a high data rate, switch off error checking and call **PI_GetError()** yourself when there is time to do so. You might want to use permanent error checking to debug your application and switch it off for normal operation. At startup of the library error checking is switched on.

Arguments:

ID ID of controller

bErrorCheck switch error checking on (**TRUE**) or off (**FALSE**)

Returns:

the old state, before this call

BOOL PI_TranslateError (int *iErrorNumber*, char* *szErrorMessage*, int *iBufferSize*)

Translate error number to error message.

Arguments:

iErrorNumber number of error, as returned from **PI_GetError()**.

szErrorMessage pointer to buffer that will store the message

iBufferSize size of the buffer

Returns:

TRUE if successful, **FALSE**, if the buffer was too small to store the message

Int PI_TryConnectRS232 (int *port*, int *baudrate*)

Starts background thread which tries to establish connection to controller with given RS-232 settings.

Arguments:

port COM port to use (e.g. 1 for "COM1")

baudrate to use

Returns:

ID of new thread (≥ 0), **error code** (< 0) if there was an error

Int PI_TryConnectUSB (const char* *szDescription*)

Starts background thread which tries to establish connection to controller with given USB settings.

Arguments:

szDescription the description of the controller returned by PI_EnumerateUSB

Returns:

ID of new thread (≥ 0), **error code** (< 0) if there was an error

4.3. Interface Settings

With `PI_InterfaceSetupDlg()`, p. 16, the *Connect* dialog is called. This dialog offers interface tab cards where you can configure and establish the connection (see descriptions below). Note that not all of the interfaces shown via the tab cards may be present on your controller.

RS-232

- **COM Port:** Select the desired COM port of the PC, something like "COM1" or "COM2". Only the ports available on the system are displayed.
- **Baud Rate:** The baud rate of the interface. The baud rate chosen will be set on both the host PC and the controller side of the interface.

USB

- Use the "Rescan" button to obtain all controllers available via USB. In the resulting list, click on the controller to which you want to connect. Use the "Serial Settings" button to specify the baudrate set with the DIP switches on the controller.

IEEE 488

- **Board ID:** ID of the National Instruments board installed (currently only National Instruments IEEE boards are supported). If only one board is installed this will be 0, as in the most cases. Use the National Instruments setup and test software to determine the board ID.
- **Device Address:** The address of the connected device. Please read the documentation of the connected device to determine its address setting and, if necessary, how to change it. The settings here and at the device must match.

TCP/IP

- Use the "Search for controllers" button to obtain all available controllers with their IP address and port settings. In the resulting list, click on the controller to which you want to connect and check that its IP address and port number are correctly transferred to the Hostname / TCP/IP Address and Port fields above the list.
- In the list, you can also identify the controllers which have already a TCP/IP connection open. If you try to connect to such a controller, an error message will arise, and no connection is possible.

5. Functions for Sending and Reading Strings

With PI library functions for GCS query commands the controller automatically continues processing subsequent functions only after the controller has retrieved the complete response from the input buffer.

This is valid for all query functions except if a query is sent as a string using `PI_Gcs_Commandset()`.

PI library functions for GCS commands are described in “Basic Functions for GCS Commands” (p. 22) and “Functions for GCS Commands for Wave Generator and DDL” (p. 115).

Example for a query function not using a string:

```
PI_qMOV (ID, "1", pdValue)
```

NOTICE

If a query command is sent as string using `PI_Gcs_Commandset()` it is necessary to make sure that the size of the response string matches the size of the input buffer. Otherwise it may happen that a response has not yet been retrieved completely before a next function is processed.

Therefore, if a query command is sent as string, it is necessary to query the size of the response string in the input buffer by sending `PI_GcsGetAnswerSize()` and to retrieve the response from input buffer by sending `PI_GcsGetAnswer()`.

The response to `PI_GcsGetAnswerSize()` determines the size (i.e., *iBufferSize*) that the input buffer (i.e., *szAxes*) must have to obtain the complete response to the query.

In some cases it can be necessary to query `PI_GetAnswerSize()` again after that, for it may take some time until the controller has delivered the complete response string. Then, it is recommended to keep querying `PI_GetAnswerSize()` until 0 is returned.

Example for a query command sent as a string:

```
PI_GcsCommandset (ID, "MOV? 1")
```

```
PI_GcsGetAnswerSize()
```

```
PI_GcsGetAnswer()
```

5.1. Overview

BOOL PI_GcsCommandset (int <i>ID</i> , const char* <i>szCommand</i>) BOOL PI_GcsGetAnswer (int <i>ID</i> , char* <i>szAnswer</i> , int <i>iBufferSize</i>) BOOL PI_GcsGetAnswerSize (int <i>ID</i> , int* <i>piAnswerSize</i>)
--

5.2. Function Description

BOOL **PI_GcsCommandset** (int *ID*, const char* *szCommand*)

Sends a GCS command to the controller. Any GCS command can be sent, but this command is intended to allow use of commands not having a function in the current version of the library.

See the User Manual of the controller for a description of the GCS commands which are understood by the controller firmware, for a command reference and for any limitations regarding the arguments of the commands.

Arguments:

ID ID of controller

szCommand the GCS command as string

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL **PI_GcsGetAnswer** (int *ID*, char* *szAnswer*, int *iBufferSize*)

Gets the answer to a GCS command, provided its length does not exceed *bufsize*. The answers to a GCS command are stored inside the DLL, where as much space as necessary is obtained. Each call to this function returns and deletes the oldest answer in the DLL.

See the User Manual of the controller for a description of the GCS commands which are understood by the controller firmware, for a command reference and for any limitations regarding the arguments of the commands.

Arguments:

ID ID of controller

szAnswer the buffer to receive the answer.

iBufferSize the size of *szAnswer*.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL **PI_GcsGetAnswerSize** (int *ID*, int* *piAnswerSize*)

Gets the size of an answer of a GCS command.

Arguments:

ID ID of controller

piAnswerSize pointer to integer to receive the size of the oldest answer waiting in the DLL.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

6. Basic Functions for GCS Commands

The functions listed in this chapter are based on the commands of the GCS. You can use a function only if the corresponding command is supported by your controller. See the user manual of the controller for the supported commands.

For all details regarding the functionality and arguments of commands, see the command descriptions in the user manual of the controller.

NOTE

If a query command is sent as string using `PI_Gcs_Commandset()` it is necessary to make sure that the size of the response string matches the size of the input buffer.

Otherwise it may happen that a response has not yet been retrieved completely before a next function is processed.

See “Functions for Sending and Reading Strings” (p. 20) for details.

6.1. Overview

Function	Short Description	Page
BOOL PI_AAP (int <i>ID</i> , const char* <i>szAxis1</i> , double <i>dLength1</i> , const char* <i>szAxis2</i> , double <i>dLength2</i> , double <i>dAlignStep</i> , int <i>iNrRepeatedPositions</i> , int <i>iAnalogInput</i>)	Automated Alignment Part	35
BOOL PI_ACC (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Set Closed-Loop Acceleration	35
BOOL PI_ADD (int <i>ID</i> , const char* <i>szVariable</i> , double <i>value1</i> , double <i>value2</i>)	Add two values and save the result to a variable	35
BOOL PI_AOS (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set an offset to the analog input for the given axis	36
BOOL PI_ATC (int <i>ID</i> , const int* <i>piChannels</i> , const int* <i>piValueArray</i> , int <i>iArraySize</i>)	Automatic calibration	36
BOOL PI_ATZ (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdLowVoltageArray</i> , const BOOL* <i>pbUseDefaultArray</i>)	Automatic zero-point calibration	36
BOOL PI_BRA (const int <i>ID</i> , char *const <i>szAxes</i> , BOOL * <i>pbValarray</i>)	Set brake on/off	37
BOOL PI_CCL (int <i>ID</i> , int <i>iCommandLevel</i> , const char* <i>szPassWord</i>)	Set command level of the controller	37
BOOL PI_CMO (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>piValueArray</i>)	Select closed-loop control mode	37
BOOL PI_CPY (int <i>ID</i> , const char* <i>szVariable</i> , const char* <i>szCommand</i>)	Copy a command response into a variable	37
BOOL PI_CST (int <i>ID</i> , const char* <i>szAxes</i> , const char* <i>szNames</i>)	Loads parameter values from a positioner database	38
BOOL PI_CTI (int <i>ID</i> , const int* <i>piTriggerInputIds</i> , const int* <i>piTriggerParameterArray</i> , const char* <i>szValueArray</i> , int <i>iArraySize</i>)	Configures the trigger input conditions	38
BOOL PI_CTO (int <i>ID</i> , const int* <i>piTriggerOutputIds</i> , const int* <i>piTriggerParameterArray</i> , const double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Configures the trigger output conditions	38

Function	Short Description	Page
BOOL PI_CTOSTring (int <i>ID</i> , const int* <i>piTriggerOutputIds</i> , const int* <i>piTriggerParameterArray</i> , const char* <i>szValueArray</i> , int <i>iArraySize</i>)	Configures the trigger output conditions	39
BOOL PI_CTR (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set target relative to current closed-loop target	39
BOOL PI_CTV (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set absolute closed-loop target	39
BOOL PI_DCO (int <i>ID</i> , const char* <i>szAxes</i> , const BOOL* <i>pbValueArray</i>)	Sets drift compensation mode for given axes	39
BOOL PI_DEC (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Set Closed-Loop Deceleration	40
BOOL PI_DEL (int <i>ID</i> , int <i>iMilliseconds</i>)	Delay The Command Interpreter	40
BOOL PI_DFH (int <i>ID</i> , const char* <i>szAxes</i>)	Defines the current position as the axis home position	40
BOOL PI_DIO (int <i>ID</i> , const int* <i>piChannelsArray</i> , const BOOL* <i>pbValueArray</i> , int <i>iArraySize</i>)	Set Digital Output Lines	40
BOOL PI_DLT (int <i>ID</i> , const char* <i>name</i>)	Deletes a data file that was saved in nonvolatile memory using PI_STD()	41
BOOL PI_DPA (int <i>ID</i> , const char* <i>szPassword</i> , const char* <i>szAxes</i> , const unsigned int* <i>iParameterArray</i>)	Resets parameters or settings to default values	41
BOOL PI_DRC (int <i>ID</i> , const int* <i>piRecordTableIdsArray</i> , const char* <i>szRecordSource</i> , const int* <i>piRecordOptionsArray</i>)	Set Data Recorder Configuration	41
BOOL PI_DRT (int <i>ID</i> , const int* <i>piRecordTableIdsArray</i> , const int* <i>piTriggerSourceArray</i> , const char* <i>szValues</i> , int <i>iArraySize</i>)	Set Data Recorder Trigger Source	41
BOOL PI_EAX (int <i>ID</i> , const char* <i>szAxes</i> , const BOOL* <i>pbValueArray</i>)	Enable Axis	42
BOOL PI_FDG (int <i>ID</i> , const char* <i>szScanRoutineName</i> , const char* <i>szScanAxis</i> , const char* <i>szStepAxis</i> , const char* <i>szParameters</i>)	Fast alignment: Defines a fast alignment gradient search routine	42
BOOL PI_FDR (int <i>ID</i> , const char* <i>szScanRoutineName</i> , const char* <i>szScanAxis</i> , const double <i>dScanAxisRange</i> , const char* <i>szStepAxis</i> , const double <i>dStepAxisRange</i> , const char* <i>szParameters</i>)	Fast alignment: Defines a fast alignment area scan routine.	43
BOOL PI_FED (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>piEdgeArray</i> , const int* <i>piParamArray</i>)	Find Edge	44
BOOL PI_FGC (int <i>ID</i> , const char* <i>szProcessIds</i> , const double* <i>pdScanAxisCenterValueArray</i> , const double* <i>pdStepAxisCenterValueArray</i>)	Fast alignment: Change center position of gradient search routine.	44
BOOL PI_FIO (int <i>ID</i> , const char* <i>szAxis1</i> , double <i>dLength1</i> , const char* <i>szAxis2</i> , double <i>dLength2</i> , double <i>dThreshold</i> , double <i>dLinearStep</i> , double <i>dAngleScan</i> , int <i>iAnalogInput</i>)	Fast Input-Output Alignment Procedure	45
BOOL PI_FLM (int <i>ID</i> , const char* <i>szAxis</i> , double <i>dLength</i> , double <i>dThreshold</i> , int <i>iAnalogInput</i> , int <i>iDirection</i>)	Fast Line Scan to Maximum	45
BOOL PI_FLS (int <i>ID</i> , const char* <i>szAxis</i> , double <i>dLength</i> , double <i>dThreshold</i> , int <i>iAnalogInput</i> , int <i>iDirection</i>)	Fast Line Scan	45
BOOL PI_FNL (int <i>ID</i> , const char* <i>szAxes</i>)	Fast Move To Negative Limit	46
BOOL PI_FPH (int <i>ID</i> , const char* <i>szAxes</i>)	Starts Phase Finding Process	46

Function	Short Description	Page
BOOL PI_FPL (int <i>ID</i> , const char* <i>szAxes</i>)	Fast Move To Positive Limit	46
BOOL PI_FRC (int <i>ID</i> , const char* <i>szProcessIDBase</i> , const char* <i>szProcessIDsCouplet</i>)	Fast alignment: Couples fast alignment routines to each other.	46
BOOL PI_FRF (int <i>ID</i> , const char* <i>szAxes</i>)	Fast Move To Reference Switch	47
BOOL PI_FRP (int <i>ID</i> , const char* <i>szScanRoutineNames</i> , const int* <i>piOptionsArray</i>)	Fast alignment: Stops, pauses or resumes a fast alignment routine.	47
BOOL PI_FRS (int <i>ID</i> , const char* <i>szScanRoutineNames</i>)	Fast alignment: Starts a fast alignment routine.	47
BOOL PI_FSA (int <i>ID</i> , const char* <i>szAxis1</i> , double <i>dLength1</i> , const char* <i>szAxis2</i> , double <i>dLength2</i> , double <i>dThreshold</i> , double <i>dDistance</i> , double <i>dAlignStep</i> , int <i>iAnalogInput</i>)	Fast Scan with Automated Alignment	47
BOOL PI_FSC (int <i>ID</i> , const char* <i>szAxis1</i> , double <i>dLength1</i> , const char* <i>szAxis2</i> , double <i>dLength2</i> , double <i>dThreshold</i> , double <i>dDistance</i> , int <i>iAnalogInput</i>)	Fast Scan with Abort	48
BOOL PI_FSF (int <i>ID</i> , const char* <i>szAxis</i> , double <i>forceValue1</i> , double <i>positionOffset</i> , BOOL <i>useForceValue2</i> , double <i>forceValue2</i>)	Start a find-surface procedure	48
BOOL PI_FSM (int <i>ID</i> , const char* <i>szAxis1</i> , double <i>dLength1</i> , const char* <i>szAxis2</i> , double <i>dLength2</i> , double <i>dThreshold</i> , double <i>dDistance</i> , int <i>iAnalogInput</i>)	Fast Scan to Maximum	49
BOOL PI_GetAsyncBuffer (int <i>ID</i> , double ** <i>pnValArray</i>)	Get address of internal buffer	49
int PI_GetAsyncBufferIndex (int <i>ID</i>)	Get index used for the internal buffer	49
BOOL PI_GetDynamicMoveBufferSize (int <i>ID</i> , long* <i>pnSize</i>)	Get Memory Space For Trajectory Points	49
BOOL PI_GOH (int <i>ID</i> , const char* <i>szAxes</i>)	Go To Home Position	50
BOOL PI_HasPosChanged (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Query for Position Change	50
BOOL PI_HDT (int <i>ID</i> , const int* <i>iDeviceIDsArray</i> , const int* <i>iAxisIDsArray</i> , const int* <i>piValueArray</i> , int <i>iArraySize</i>)	Set HID Default Lookup Table	50
BOOL PI_HIA (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>iFunctionArray</i> , const int* <i>iDeviceIDsArray</i> , const int* <i>iAxisIDsArray</i>)	Configure Control Done By HID Axis	50
BOOL PI_HIL (int <i>ID</i> , const int* <i>iDeviceIDsArray</i> , const int* <i>iLED_IDsArray</i> , const int* <i>pnValueArray</i> , int <i>iArraySize</i>)	Set State Of HID LED	51
BOOL PI_HIN (int <i>ID</i> , const char* <i>szAxes</i> , const BOOL* <i>pbValueArray</i>)	Set Activation State For HID Control	51
BOOL PI_HIS (int <i>ID</i> , const int* <i>iDeviceIDsArray</i> , const int* <i>iItemIDsArray</i> , const int* <i>iPropertyIDArray</i> , const char* <i>szValues</i> , int <i>iArraySize</i>)	Configure HI Device	51
BOOL PI_HIT (int <i>ID</i> , const int* <i>piTableIDsArray</i> , const int* <i>piPointNumberArray</i> , const double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Fill HID Lookup Table	51
BOOL PI_HLT (int <i>ID</i> , const char* <i>szAxes</i>)	Halt Motion Smoothly	52
BOOL PI_IFC (int <i>ID</i> , const char* <i>szParameters</i> , const char* <i>szValues</i>)	Interface configuration in volatile memory	52
BOOL PI_IFS (int <i>ID</i> , const char* <i>szPassword</i> , const char* <i>szParameters</i> , const char* <i>szValues</i>)	Interface parameter store in non-volatile memory	52

Function	Short Description	Page
BOOL PI_IMP (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdImpulseSize</i>)	Starts performing an impulse and recording the impulse response	53
BOOL PI_IsAvailable (int <i>ID</i>)	Checks if the controller is “available” and ready to respond	53
BOOL PI_IsControllerReady (int <i>ID</i> , int* <i>piControllerReady</i>)	Asks controller for ready status	53
BOOL PI_IsMoving (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Check if axes are moving	54
BOOL PI_IsRunningMacro (int <i>ID</i> , BOOL* <i>pbRunningMacro</i>)	Check if controller is currently running a macro	54
BOOL PI_JAX (int <i>ID</i> , int <i>iJoystickID</i> , const int <i>iAxesID</i> , const char* <i>szAxesIDs</i>)	Set Axis Controlled By Joystick	54
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BOOL PI_qOVF (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbOverflow</i>)	Checks overflow status	88
BOOL PI_qOVL (int <i>ID</i> , const int* <i>piPIEZOWALKChannelsArray</i> , double* <i>pdValueArray</i>)	Get Open-Loop Velocity	88

Function	Short Description	Page
BOOL PI_qPLM (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get High Position Soft Limit	88
BOOL PI_qPOS (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Real Position	89
BOOL PI_qPUN (int <i>ID</i> , const char* <i>szAxes</i> , char* <i>szUnit</i> , int <i>iBufferSize</i>)	Get the Position Units	89
BOOL PI_qRMC (int <i>ID</i> , char * <i>szBuffer</i> , int <i>iBufferSize</i>)	List Running Macros	89
BOOL PI_qRON (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Get Reference Mode	89
BOOL PI_qRTD (int <i>ID</i> , int <i>tableType</i> , int <i>tableID</i> , int <i>infoID</i> , char* <i>buffer</i> , int <i>bufsize</i>)	Reads the content of a data table in volatile memory	89
BOOL PI_qRTO (int <i>ID</i> , const char* <i>szAxes</i> , int* <i>pbValueArray</i>)	Read the "ready-for-turn-off state"	90
BOOL PI_qRTR (int <i>ID</i> , int* <i>piRecordTableRate</i>)	Get Record Table Rate	90
BOOL PI_qSAI (int <i>ID</i> , char* <i>szAxes</i> , int <i>iBufferSize</i>)	Get List Of Current Axis Identifiers	90
BOOL PI_qSAI_ALL (int <i>ID</i> , char* <i>szAxes</i> , int <i>iBufferSize</i>)	Get List Of Current Axis Identifiers	90
BOOL PI_qSCT (int <i>ID</i> , double* <i>pdCycleTime</i>)	Get Cycle Time	91
BOOL PI_qSEP (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>piParameterArray</i> , double* <i>pdValueArray</i> , char* <i>szStrings</i> , int <i>iMaximumStringSize</i>)	Get Nonvolatile Memory Parameters	91
BOOL PI_qSGA (int <i>ID</i> , const int* <i>piAnalogChannelIds</i> , int* <i>piGainValues</i> , int <i>iArraySize</i>)	Get Gain	91
BOOL PI_qSIC (int <i>ID</i> , const int* <i>piFastAlignmentInputIdsArray</i> , int <i>iNumberOfInputIds</i> , char* <i>szBuffer</i> , int <i>iBufferSize</i>)	Fast alignment: Gets the calculation settings for the given fast alignment input channel	92
BOOL PI_qSMO (int <i>ID</i> , char *const <i>szAxes</i> , int * <i>pnValueArray</i>)	Get Control Value	92
BOOL PI_qSPA (int <i>ID</i> , const char* <i>szAxes</i> , unsigned int* <i>piParameterArray</i> , double* <i>pdValueArray</i> , char* <i>szStrings</i> , int <i>iMaxNameSize</i>)	Get Volatile Memory Parameters	92
BOOL PI_qSPI (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Pivot Point	92
BOOL PI_qSRG (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>iRegisterArray</i> , int * <i>iValArray</i>)	Query Status Register Value	93
BOOL PI_qSSA (int <i>ID</i> , const int* <i>iPIEZOWALKChannels</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get Step Amplitude	93
BOOL PI_qSSL (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Get Soft Limit Status	93
BOOL PI_qSSN (int <i>ID</i> , char* <i>szSerialNumber</i> , int <i>iBufferSize</i>)	Get Device Serial Number	93
BOOL PI_qSST (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Step Size	94
BOOL PI_qSTE (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get last sent step size	94
BOOL PI_qSVA (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Returns last valid open-loop control value	94
BOOL PI_qSVO (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Get Servo State (Open-Loop / Closed-Loop Operation)	94
BOOL PI_qTAC (int <i>ID</i> , int * <i>piNrChannels</i>)	Tell Analog Channels	94

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BOOL PI_qTAD (int <i>ID</i> , const int* <i>piSensorChannelsArray</i> , int* <i>piValueArray</i> , int <i>iArraySize</i>)	Returns ADC value	95
BOOL PI_qTAV (int <i>ID</i> , const int* <i>piChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get Analog Input Voltage	95
BOOL PI_qTCI (int <i>ID</i> , const int* <i>piFastAlignmentInputIDsArray</i> , double* <i>pdCalculatedInputValueArray</i> , int <i>iArraySize</i>)	Fast alignment: Gets calculated value of given fast alignment input channel.	95
BOOL PI_qTCV (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Commanded Closed-Loop Velocity	95
BOOL PI_qTGL (int <i>ID</i> , const int* <i>piTrajectoriesArray</i> , int* <i>iTrajectorySizesArray</i> , int <i>iArraySize</i>)	Motion paths: Queries the number of points in the trajectory buffer	96
BOOL PI_qTGT (int <i>ID</i> , const int* <i>iTrajectoryTiming</i>)	Motion paths: Queries the timing for trajectories.	96
BOOL PI_qTIO (int <i>ID</i> , int* <i>piInputNr</i> , int* <i>piOutputNr</i>)	Tell Digital I/O Lines	96
BOOL PI_qTMN (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Minimum Commandable Position	96
BOOL PI_qTMX (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Maximum Commandable Position	97
BOOL PI_qTNR (int <i>ID</i> , int* <i>piNumberOfRecordTables</i>)	Get Number Of Record Tables	97
BOOL PI_qTNS (int <i>ID</i> , const int* <i>piSensorChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Returns normalized sensor value for the specified sensor number	97
BOOL PI_qTPC (int <i>ID</i> , int* <i>piNumberOfPiezoChannels</i>)	Get the number of output signal channels available on the controller.	97
BOOL PI_qTRA (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdComponents</i> , double* <i>pdValueArray</i>)	Get maximum absolute position which can be reached from the current position	97
BOOL PI_qTRI (int <i>ID</i> , const int* <i>piTriggerInputIDs</i> , BOOL* <i>pbTriggerState</i> , int <i>iArraySize</i>)	Get Trigger Input State	98
BOOL PI_qTRO (int <i>ID</i> , const int* <i>piTriggerOutputIDs</i> , BOOL* <i>pbTriggerState</i> , int <i>iArraySize</i>)	Get Trigger Output State	98
BOOL PI_qTRS (int <i>ID</i> , const char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Indicate Reference Switch	98
BOOL PI_qTSC (int <i>ID</i> , int* <i>piNumberOfSensorChannels</i>)	Get the number of input signal channels available on the controller.	99
BOOL PI_qTSP (int <i>ID</i> , const int* <i>piSensorChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Requests the current position of the given input signal channel	99
BOOL PI_qTVI (int <i>ID</i> , char* <i>szBuffer</i> , int <i>iBufferSize</i>)	Tell Valid Character Set For Axis Identifiers	99
BOOL PI_qVAR (int <i>ID</i> , const char* <i>szVariables</i> , char* <i>szValues</i> , int <i>iBufferSize</i>)	Get Variable Values	99
BOOL PI_qVCO (int <i>ID</i> , char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Get Velocity Control Mode	100
BOOL PI_qVEL (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Get Closed-Loop Velocity	100
BOOL PI_qVER (int <i>ID</i> , char* <i>szVersion</i> , int <i>iBufferSize</i>)	Get Version	100
BOOL PI_qVLS (int <i>ID</i> , double* <i>pdSystemVelocity</i>)	Get System Velocity	100
BOOL PI_qVMA (int <i>ID</i> , const int* <i>piPiezoChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get Voltage Output High Limit	100

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BOOL PI_qVMI (int <i>ID</i> , const int* <i>piPiezoChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get Voltage Output Low Limit	101
BOOL PI_qVMO (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValarray</i> , BOOL* <i>pbMovePossible</i>)	Virtual Move	101
BOOL PI_qVOL (int <i>ID</i> , const int* <i>piPiezoChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get current piezo output voltages	101
BOOL PI_qVST (int <i>ID</i> , char * <i>szBuffer</i> , int <i>iBufferSize</i>)	Get the names of the available positioner types	102
BOOL PI_RBT (int <i>ID</i>)	Reboot System	102
BOOL PI_RNP (int <i>ID</i> , const int* <i>piPIEZOWALKChannelsArray</i> , const double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Relax PiezoWalk Piezos	102
BOOL PI_RON (const int <i>ID</i> , char *const <i>szAxes</i> , BOOL * <i>pbValarray</i>)	Set Reference Mode	102
BOOL PI_RPA (int <i>ID</i> , const char* <i>szAxes</i> , const int* <i>piParameterArray</i>)	Reset Volatile Memory Parameters	103
BOOL PI_RTD (int <i>ID</i> , int <i>tableType</i> , int <i>tableID</i> , const char* <i>name</i>)	Reads the content of a data file in nonvolatile memory and writes it to a given table in volatile memory	103
BOOL PI_RTO (int <i>ID</i> , const char* <i>szAxes</i>)	Make Ready to Turn OFF	103
BOOL PI_RTR (int <i>ID</i> , int <i>iRecordTableRate</i>)	Set Record Table Rate	103
BOOL PI_SAI (int <i>ID</i> , char *const <i>szOldAxes</i> , char *const <i>szNewAxes</i>)	Set Current Axis Identifiers	104
BOOL PI_SCT (int <i>ID</i> , double <i>dCycleTime</i>)	Set Cycle Time	104
BOOL PI_SEP (int <i>ID</i> , const char* <i>szPassword</i> , const char* <i>szAxes</i> , const int* <i>piParameterArray</i> , const double* <i>pdValueArray</i> , const char* <i>szStrings</i>)	Set Nonvolatile Memory Parameters	104
BOOL PI_SGA (int <i>ID</i> , const int* <i>piAnalogChannelIds</i> , const int* <i>piGainValues</i> , int <i>iArraySize</i>)	Set Gain	105
BOOL PI_SIC (int <i>ID</i> , int <i>iFastAlignmentInputId</i> , int <i>iCalcType</i> , const double* <i>pdParameters</i> , int <i>iNumberOfParameters</i>)	Fast alignment: Defines calculation settings for the given fast alignment input channel	105
BOOL PI_SMO (int <i>ID</i> , char *const <i>szAxes</i> , int * <i>pnVaueAarray</i>)	Set Open-Loop Control Value	105
BOOL PI_SPA (int <i>ID</i> , const char* <i>szAxes</i> , const unsigned int* <i>piParameterArray</i> , const double* <i>pdValueArray</i> , const char* <i>szStrings</i>)	Set Volatile Memory Parameters	105
BOOL PI_SPI (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set Pivot Point	106
BOOL PI_SSA (int <i>ID</i> , const int* <i>piPIEZOWALKChannelsArray</i> , const double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Set Step Amplitude	106
BOOL PI_SSL (int <i>ID</i> , const char* <i>szAxes</i> , const BOOL* <i>pbValueArray</i>)	Set Soft Limit	106
BOOL PI_SST (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set Step Size	107
BOOL PI_STD (int <i>ID</i> , int <i>tableType</i> , int <i>tableID</i> , const char* <i>data</i>)	Saves the content of a given table from volatile memory to a data file in nonvolatile memory	107
BOOL PI_STE (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdStepSize</i>)	Start Step And Response – Measurement	107
BOOL PI_StopAll (int <i>ID</i>)	Stop All Axes	107

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BOOL PI_STP (int <i>ID</i>)	Stop All Motion	108
BOOL PI_SVA (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Set absolute open-loop control value to move the axis	108
BOOL PI_SVO (int <i>ID</i> , const char* <i>szAxes</i> , const BOOL* <i>pbValueArray</i>)	Set Servo State (Open-Loop / Closed-Loop Operation)	108
BOOL PI_SVR (int <i>ID</i> , const char* <i>szAxes</i> , double* <i>pdValueArray</i>)	Set open-loop control value relative to the current open-loop control value to move the axis	108
BOOL PI_TGA (int <i>ID</i> , const int* <i>piTrajectoriesArray</i> , const double* <i>pdValarray</i> , int <i>iArraySize</i>)	Motion paths: Loads trajectory points to the buffer	108
BOOL PI_TGC (int <i>ID</i> , const int* <i>piTrajectoriesArray</i> , int <i>iArraySize</i>)	Motion paths: Deletes trajectory points in the buffer	109
BOOL PI_TGF (int <i>ID</i> , const int* <i>piTrajectoriesArray</i> , int <i>iArraySize</i>)	Motion paths: Completes the trajectory execution	109
BOOL PI_TGS (int <i>ID</i> , const int* <i>piTrajectoriesArray</i> , int <i>iArraySize</i>)	Motion paths: Starts trajectory execution	110
BOOL PI_TGT (int <i>ID</i> , int <i>iTrajectoryTiming</i>)	Motion paths: Sets the timing for trajectories	110
BOOL PI_TRI (int <i>ID</i> , const int* <i>piTriggerInputIds</i> , const BOOL* <i>pbTriggerState</i> , int <i>iArraySize</i>)	Enables or disables the trigger input mode	111
BOOL PI_TRO (int <i>ID</i> , const int* <i>piTriggerOutputIds</i> , const BOOL* <i>pbTriggerState</i> , int <i>iArraySize</i>)	Enables or disables the trigger output mode	111
BOOL PI_TSP (int <i>ID</i> , const int* <i>piSensorChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Sets current position of input signal channel	111
BOOL PI_VAR (int <i>ID</i> , const char* <i>szVariables</i> , const char* <i>szValues</i>)	Set Variable Value	112
BOOL PI_VCO (int <i>ID</i> , char* <i>szAxes</i> , BOOL* <i>pbValueArray</i>)	Set Velocity Control Mode	112
BOOL PI_VEL (int <i>ID</i> , const char* <i>szAxes</i> , const double* <i>pdValueArray</i>)	Set Closed-Loop Velocity	112
BOOL PI_VLS (int <i>ID</i> , double <i>dSystemVelocity</i>)	Set System Velocity	112
BOOL PI_VMA (int <i>ID</i> , const int* <i>piPiezoChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Set Voltage Output High Limit	113
BOOL PI_VMI (int <i>ID</i> , const int* <i>piPiezoChannelsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Set Voltage Output Low Limit	113
BOOL PI_WAC (int <i>ID</i> , char* <i>szCondition</i>)	Wait For Condition For Macro Execution	113
BOOL PI_WPA (int <i>ID</i> , const char* <i>szPassword</i> , const char* <i>szAxes</i> , const int* <i>piParameterArray</i>)	Save Parameters To Nonvolatile Memory	113

6.2. Function Description

The functions listed in this chapter are based on the commands of the GCS. You can use a function only if the corresponding command is supported by your controller. See the user manual of the controller for the supported commands.

For all details regarding the functionality and arguments of commands, see the command descriptions in the user manual of the controller.

See "Function Calls" (p. 10) for some general notes about the argument syntax.

BOOL PI_AAP (int *ID*, const char* *szAxis1*, double *dLength1*, const char* *szAxis2*, double *dLength2*, double *dAlignStep*, int *iNrRepeatedPositions*, int *iAnalogInput*)

Corresponding command: AAP

Starts a scanning procedure for better determination of the maximum intensity of an analog input signal.

The scanning procedure started with PI_AAP() corresponds to the "fine portion" of the scanning procedure that was started with PI_FSA().

Arguments:

ID ID of controller

szAxis1 first axis that defines scanning area

dLength1 length of scanning area along *szAxis1*

szAxis2 second axis that defines scanning area

dLength2 length of scanning area along *szAxis2*

dAlignStep starting value for the step size

iNrRepeatedPositions number of successful checks of the local maximum at the current position that is required for successfully completing

iAnalogInput is the identifier of the analog input signal whose maximum intensity is sought

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_ACC (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: ACC

Set the acceleration to use during moves of *szAxes*. The PI_ACC() setting only takes effect when the given axis is in closed-loop operation (servo on).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray maximum accelerations for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_ADD (int *ID*, const char* *szVariable*, double *value1*, double *value2*)

Corresponding command: ADD

Add two values and save the result to a variable.

Arguments:

ID ID of controller

szVariable name of variable to store the result

value1 first value to be added

value2 second value to be added

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_AOS (int *ID*, const char* *szAxes*, const double* *pdValueArray*)**Corresponding command:** AOS

Set an offset to the analog input for the given axis.

Arguments:*ID* ID of controller*szAxes* string with axes*pdValueArray* analog offset for the axes.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_ATC** (int *ID*, const int* *piChannels*, const int* *piValueArray*, int *iArraySize*)**Corresponding command:** ATC

Automatic calibration.

See "Calibration Settings" and the description of the ATC command in the User Manual of the controller for more information.

Arguments:*ID* ID of controller*piChannels* string with channels of the piezo control electronics*piValueArray* comprises the settings to be calibrated.*iArraySize* size of arrays**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_ATZ** (int *ID*, const char* *szAxes*, const double* *pdLowVoltageArray*, const **BOOL*** *pbUseDefaultArray*)**Corresponding command:** ATZAutomatic zero-point calibration for *szAxes*. Sets the output voltage which is to be applied at the zero position of the axis and starts an appropriate calibration procedure.

NOTICE: The AutoZero procedure will move the axis, and the motion may cover the whole travel range. Make sure that it is safe for the positioner to move.

See "AutoZero Procedure" and the description of the ATZ command in the User Manual of the controller for more information.

Arguments:*ID* ID of controller*szAxes* string with axes*pdLowVoltageArray* Array with low voltages for the corresponding axes.*pbUseDefaultArray* If **TRUE** the value in *pdLowVoltageArray* for the axis is ignored and the value stored in the controller (Autozero Low Voltage parameter, ID 0x07000A00) is used.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)

BOOL PI_BRA (const int *ID*, char *const *szAxes*, BOOL * *pbValarray*)

Corresponding command: BRA

Set brake state for *szAxes* to on (**TRUE**) or off (**FALSE**).

Arguments:

ID ID of controller

szAxes string with axes

pbValarray modes for the specified axes, **TRUE** for on, **FALSE** for off

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_CCL (int *ID*, int *iCommandLevel*, const char* *szPassWord*)

Corresponding command: CCL

If *Password* is correct, this function sets the *CommandLevel* of the controller and determines thus the availability of commands and the write access to the system parameters. Use PI_qHLP() to determine which commands are available in the current command level. PI_qHPA() lists the parameters including the information about which command level allows write access to them.

Arguments:

ID ID of controller

iCommandLevel can be

0 = the default setting, all commands provided for "normal" users are available, read access to all parameters

1 = provides additional commands and write access to level-1-parameters (commands and parameters from level 0 are included).

szPassWord password for CCL 1 is "ADVANCED", for CCL 0 no password is required

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_CMO (int *ID*, const char* *szAxes*, const int* *piValueArray*)

Corresponding command: CMO

Select closed-loop control mode. The selection determines the controlled variable (e.g. position or velocity or force).

The currently valid target value for the controlled variable can be queried with PI_qCTV(). An absolute target for the controlled variable can be set with PI_CTV(), a relative target can be set with PI_CTR(). The current value of the controlled variable can be queried with PI_qCAV().

ID ID of controller

szAxes string with axes

piValueArray modes for the specified axes

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_CPY (int *ID*, const char* *szVariable*, const char* *szCommand*)

Corresponding command: CPY

Copy a command response into a variable.

Arguments:

ID ID of controller

szVariable name of variable

szCommand query command, the result is stored in the variable given

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_CST (int *ID*, const char* *szAxes*, const char* *szNames*)

Corresponding command: CST

Loads the specific values for the *szNames* positioner from a positioner database (see also p. 130) and sends them to the controller so that the controller parameters are properly adjusted to the connected mechanics. The permissible positioner types can be listed with the PI_qVST() function.

The following actions are included with PI_CST():

- Sets the servo off
- Loads parameter values from positioner database and sends them to the controllers RAM using PI_SPA()
- Checks the error

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Note that the assignment of a positioner type with PI_CST() is only permissible for axes A and B. The behavior of the function differs depending on the current versions of the controller firmware and PI GCS 2 DLL. For further details, see p. 135.

Arguments:

ID ID of controller

szAxes identifiers of the axes

szNames the names of the positioners separated by '\n' ("line-feed"), the names must be present in one of the positioner database files

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_CTI (int *ID*, const int* *piTriggerInputIds*, const int* *piTriggerParameterArray*, const char* *szValueArray*, int *iArraySize*)

Corresponding command: CTI

Configures the trigger input conditions for the given digital input line. Depending on the controller, the trigger input conditions will either become active immediately, or will become active when activated with PI_TRI().

Arguments:

ID ID of controller

piTriggerInputIds is an array with the trigger input lines of the controller

piTriggerParameterArray is an array with the CTI parameter IDs

szValueArray is a list of the values to which the CTI parameters are set. The single values must be separated by a linefeed character

iArraySize is the size of the array *piTriggerInputIds*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_CTO (int *ID*, const int* *piTriggerOutputIds*, const int* *piTriggerParameterArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: CTO

Configures the trigger output conditions for the given digital output line. Depending on the controller, the trigger output conditions will either become active immediately, or will become active when activated with PI_TRO().

Arguments:

ID ID of controller

piTriggerOutputIds is an array with the trigger output lines of the controller

piTriggerParameterArray is an array with the CTO parameter IDs

pdValueArray is an array of the values to which the CTO parameters are set

iArraySize is the size of the array *piTriggerOutputIds*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_CTOSTring (int ID, const int* piTriggerOutputIds, const int*
piTriggerParameterArray, const char* szValueArray, int iArraySize)

```

Corresponding command: CTO

Configures the trigger output conditions for the given digital output line. Depending on the controller, the trigger output conditions will either become active immediately, or will become active when activated with PI_TRO().

Arguments:

ID ID of controller

piTriggerOutputIds is an array with the trigger output lines of the controller

piTriggerParameterArray is an array with the CTO parameter IDs

szValueArray is a list of the values to which the CTO parameters are set. The single values must be separated by a linefeed character

iArraySize is the size of the array *piTriggerOutputIds*

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_CTR (int ID, const char* szAxes, const double* pdValueArray)

```

Corresponding command: CTR

Set relative closed-loop target *for* *szAxes*. Moves the given axes. All axes start moving simultaneously. Servo must be enabled for all commanded axes prior to using this command.

The selected closed-loop control mode (see PI_CMO()) determines the variable which is controlled with PI_CTR() (e.g. position or velocity or force).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray relative target values for the axes

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_CTV (int ID, const char* szAxes, const double* pdValueArray)

```

Corresponding command: CTV

Set absolute closed-loop target *for* *szAxes*. Moves the given axes. All axes start moving simultaneously. Servo must be enabled for all commanded axes prior to using this command.

The selected closed-loop control mode (see PI_CMO()) determines the variable which is controlled with PI_CTV() (e.g. position or velocity or force).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray target values for the axes

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_DCO (int ID, const char* szAxes, const BOOL* pbValueArray)

```

Corresponding command: DCO

Sets drift compensation mode for given axes (on or off). Drift compensation is applied to avoid unwanted changes in displacement over time and is therefore recommended for static operation. For a detailed description see "Drift Compensation" in the controller User Manual.

Drift compensation is automatically deactivated as long as the wave generator is activated.

Arguments:**ID** ID of controller**szAxes** string with axes**pbValueArray** gives the drift compensation mode, can have the following values:

0 = drift compensation off

1 = drift compensation on

Returns:**TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_DEC** (int *ID*, const char* *szAxes*, double* *pdValueArray*)**Corresponding command:** DECSet the deceleration to use during moves of *szAxes*. The PI_DEC() setting only takes effect when the given axis is in closed-loop operation (servo on).**Arguments:****ID** ID of controller**szAxes** string with axes**pdValueArray** maximum decelerations for the axes**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_DEL** (int *ID*, int *iMilliseconds*)**Corresponding command:** DELDelay the controller for *iMilliseconds* milliseconds.**Arguments:****ID** ID of controller**iMilliseconds** delay value in milliseconds**Returns:****TRUE** if successful, **FALSE** otherwise**BOOL PI_DFH** (int *ID*, const char* *szAxes*)**Corresponding command:** DFHDefines the current positions of *szAxes* as the axis home position (by setting the position value to 0.00).**Arguments:****ID** ID of controller**szAxes** string with axes, if "" or **NULL** all axes are affected.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_DIO** (int *ID*, const int* *piChannelsArray*, const BOOL* *pbValueArray*, int *iArraySize*)**Corresponding command:** DIO

Set digital output channels HIGH or LOW.

Arguments:**ID** ID of controller**piChannelsArray** array containing digital output channel identifiers**pbValueArray** array containing the states of specified digital output channels, **TRUE** if HIGH, **FALSE** if LOWIf *piChannelsArray* contains 0, the array is a bit pattern which gives the states of all lines

iArraySize the size of the array *pbValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_DLT (int *ID*, const char* *name*)

Corresponding command: DLT

Deletes a data file that was saved in nonvolatile memory using PI_STD().

Arguments:

ID ID of controller

name is the file name

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_DPA (int *ID*, const char* *szPassWord*, const char* *szAxes*, const int* *piParameterArray*)

Corresponding command: DPA

Resets parameters or settings to default values. DPA does not overwrite parameters or parameter-independent settings in non-volatile memory.

Arguments:

ID ID of controller

szPassWord The password depends on the parameter or parameter-independent setting to be resetted. See the user manual of the controller for details.

szAxes string with designators. For each designator in *szAxes* one parameter value is reset.

piParameterArray Array with parameter IDs

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_DRC (int *ID*, const int* *piRecordTableIdsArray*, const char* *szRecordSourceIds*, const int* *piRecordOptionsArray*)

Corresponding command: DRC

Set data recorder configuration: determines the data source (*szRecordSourceIdsArray*) and the kind of data (*piRecordOptionsArray*) used for the given data recorder table.

Arguments:

ID ID of controller

piRecordTableIdsArray ID of the record table

szRecordSourceIds ID of the record source, for example axis number or channel number. The value of this argument depends on the corresponding record option.

piRecordOptionsArray record option, i.e. the kind of data to be recorded

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_DRT (int *ID*, const int* *piRecordTableIdsArray*, const int* *piTriggerSourceArray*, const char* *szValues*, int *iArraySize*)

Corresponding command: DRT

Defines a trigger source for the given data recorder table.

For the data recorder configuration, i.e. for the assignment of data sources and record options to the recorder tables, use PI_DRC().

With PI_qDRR() you can read the last recorded data set.

For more information see "Data Recorder" in the controller User Manual.

Arguments:

ID ID of controller

piRecordTableIdsArray ID of the record table

piTriggerSourceArray ID of the trigger source

szValues depending on the trigger source, value can be a dummy, e.g. an arbitrary character, or the ID of a certain digital input line

iArraySize size of *piRecordTableIdsArray*, *piTriggerSourceArray* and *szValues*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_EAX (int *ID*, const char* *szAxes*, const BOOL* *pbValueArray*)

Corresponding command: EAX

Enable axis. If disabled, no motion is executed. If motion is commanded for an axis that is not enabled, an error will be set.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray enable status for the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FDG (int *ID*, const char* *szScanRoutineName*, const char* *szScanAxis*, const char* *szStepAxis*, const char* *szParameters*)

Corresponding command: FDG

Fast alignment: Defines a fast alignment gradient search routine. Use PI_FRS to start the routine. With PI_qFRR(), you can read out the definition and the results of the routine.

See the E712T0016 Technical Note ("Fast Alignment Routines") for detailed descriptions.

Arguments:

ID ID of controller

szScanRoutineName The identifier of the routine.

szScanAxis Identifier of the axis that is to be the master axis of the gradient search routine.

szStepAxis Identifier of the axis that is to be the second axis of the gradient search routine.

szParameters The parameters are optional. For parameters that are omitted, default values will be used.

[ML <stop level>] // float

ML: Required keyword

<stop level>: Gives one stop criterion for the gradient search routine.

[A <alignment signal input channel>] // int

A: Required keyword

<alignment signal input channel>: Identifier of the fast alignment input channel whose maximum intensity is sought.

[MIA <min radius>] // float

MIA: Required keyword

<min radius>: Minimum radius of the circular motion for scan axis and step axis (= amplitude of the sine curve).

[MAA <max radius>] // float

MAA: Required keyword

<max radius>: Maximum radius of the circular motion for scan axis and step axis (= amplitude of the sine curve).

[F <frequency>] // float

F: Required keyword

<frequency>: Frequency of the sine curves for scan axis and step axis.

[SP <speed factor>] // float

SP: Required keyword

<speed factor>: The speed factor can be used to speed up the offset change.

[V <max velocity>] // float
 V: Required keyword
 <max velocity>: Velocity limit for the offset change..
 [MDC <max direction changes>] // int
 MDC: Required keyword
 <max direction changes>: Gives one stop criterion for the gradient search routine.
 [SPO <speed offset>] // float
 SPO: Required keyword
 <speed offset>: Offset that can be applied in the velocity calculation.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FDR (int *ID*, const char* *szScanRoutineName*, const char* *szScanAxis*, const double *dScanAxisRange*, const char* *szStepAxis*, const double *dStepAxisRange*, const char* *szParameters*)

Corresponding command: FDR

Fast alignment: Defines a fast alignment area scan routine. Use PI_FRS to start the routine. With PI_qFRR(), you can read out the definition and the results of the routine.

See the E712T0016 Technical Note ("Fast Alignment Routines") for detailed descriptions.

Arguments:

ID ID of controller
szScanRoutineName The identifier of the routine.
szScanAxis Identifier of the axis that is to be the master axis of the scan routine.
dScanAxisRange Scan range for the scan axis.
szStepAxis Identifier of the step axis.
dStepAxisRange Scan range for the step axis.
szParameters The parameters are optional. For parameters that are omitted, default values will be used.

[L <threshold level>] // float
 L: Required keyword
 Minimum intensity threshold of the analog input signal. If during an area scan routine no value of the analog input signal is higher than the given minimum threshold level, PI_qFRR() will report "not successful" for the routine.

[A <alignment signal input channel>] // int
 A: Required keyword
 <alignment signal input channel>: Identifier of the fast alignment input channel whose maximum intensity is sought.

[F <frequency>] // float
 F: Required keyword
 Frequency of the scan axis.

[V <velocity>] // float
 V: Required keyword
 <velocity>: Velocity of the step axis.

[MP1 <scan axis middle position>] // float
 MP1: Required keyword
 <scan axis middle position>: Middle position of the scan range for the scan axis.

[MP2 <step axis middle position>] // float
 MP2: Required keyword
 <step axis middle position>: Middle position of the scan range for the step axis.

[TT <target type>] // int
 TT: Required keyword
 <target type>: ID of the area scan type. Possible values:
 0 = raster scan
 1 = spiral scan

[CM <estimation method>] // int
 CM: Required keyword
 <estimation method>: ID of the estimation method for the position of the global intensity maximum:

0 = global maximum is at the position where the maximum value was recorded
 1 = position of global maximum is calculated from the recorded data using a Gaussian LS fit.
 2 = position of global maximum is calculated from the recorded data using an analogy to a center-of-gravity calculation

[MIIL <minimum level of fast alignment input>] // float

MIIL: Required keyword

<minimum level of fast alignment input>: Minimum intensity to be used for estimation method 1 or 2 (see CM above), in % of the maximum intensity that has been recorded.

[MAIL <maximum level of fast alignment input>] // float

MAIL: Required keyword

<maximum level of fast alignment input>: Maximum intensity to be used for estimation method 1 or 2 (see CM above), in % of the maximum intensity that has been recorded.

[SP <stop position option>] // int

SP: Required keyword

<stop position option>: ID of the position to be approached by scan axis and step axis when the area scan routine has been completed:

0 = move to scan axis and step axis position with the maximum intensity of the analog input signal

1 = stay at the end position of the area scan routine

2 = move to the start position of the area scan routine

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_FED (int *ID*, const char* *szAxes*, const int* *iEdgeArray*, const int* *iParamArray*)

Corresponding command: FED

Moves given axis to a given signal edge and then moves out of any limit condition.

Arguments:

ID ID of controller

szAxes axes to move.

iEdgeArray Defines the type of edge the axis has to move to.

The following edge types are available:

1 = negative limit switch

2 = positive limit switch

3 = reference switch

iParamArray at present, this argument is not needed, should contain zeros

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_FGC(int *ID*, const char* *szProcessIds*, const double* *pdScanAxisCenterValueArray*, const double* *pdStepAxisCenterValueArray*)

Corresponding command: FGC

Fast alignment: Change center position of gradient search routine.

Arguments:

ID ID of controller

szProcessIds The identifier of the routine.

pdScanAxisCenterValueArray Center position of the circular motion for the scan axis.

pdStepAxisCenterValueArray Center position of the circular motion for the step axis.

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_FIO (int *ID*, const char* *szAxis1*, double *dLength1*, const char* *szAxis2*, double *dLength2*, double *dThreshold*, double *dLinearStep*, double *dAngleScan*, int *iAnalogInput*)

Corresponding command: FIO

Starts a scanning procedure for the alignment of optical elements (e.g. optical fibers), the input and output of which are on the same side.

Arguments:

ID ID of controller

szAxis1 first axis that defines scanning area

dLength1 length of scanning area along *szAxis1*

szAxis2 second axis that defines scanning area

dLength2 length of scanning area along *szAxis2*

dThreshold intensity threshold of the analog input signal, in V

dLinearStep step size in which the platform moves along the spiral path

dAngleScan angle around the pivot point at which scanning is done, in degrees

iAnalogInput is the identifier of the analog input signal whose maximum intensity is sought

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FLM (int *ID*, const char* *szAxis*, double *dLength*, double *dThreshold*, int *iAnalogInput*, int *iDirection*)

Corresponding command: FLM

Starts a scanning procedure to determine the global maximum intensity of an analog input signal.

Arguments:

ID ID of controller

szAxis one axis of the controller, axes X, Y, Z, U, V, W are permissible

dLength distance to be scanned along the axis

dThreshold intensity threshold of the analog input signal, in V

iAnalogInput is the identifier of the analog input signal whose maximum intensity is sought

iDirection indicates the direction of the scanning procedure as well as the starting and end position of the distance

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FLS (int *ID*, const char* *szAxis*, double *dLength*, double *dThreshold*, int *iAnalogInput*, int *iDirection*)

Corresponding command: FLS

Starts a scanning procedure which scans a specified distance along an axis until the analog input signal reaches a specified intensity threshold.

Arguments:

ID ID of controller

szAxis one axis of the controller, axes X, Y, Z, U, V, W are permissible

dLength distance to be scanned along the axis

dThreshold intensity threshold of the analog input signal, in V

iAnalogInput is the identifier of the analog input signal whose maximum intensity is sought

iDirection indicates the direction of the scanning procedure as well as the starting and end position of the distance

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FNL (int *ID*, const char* *szAxes*)**Corresponding command:** FNL

Starts a reference move: Moves all axes *szAxes* synchronously to the negative physical limits of their travel ranges and sets the current positions to the negative range limit values.

Note: Call `PI_IsControllerReady()` to find out if referencing is complete (the controller will be "busy" while referencing, so most other commands will cause a `PI_CONTROLLER_BUSY` error) and `PI_qFRF()` to check whether the reference move was successful.

Arguments:

ID ID of controller

szAxes axes to move

Returns:

TRUE if successful, **FALSE** otherwise

Errors:

PI_UNKNOWN_AXIS_IDENTIFIER cAxis is not a valid axis identifier

BOOL PI_FPH (int *ID*, const char* *szAxes*)**Corresponding command:** FPH

Starts phase finding process: Finds offset between motor and encoder by performing a homing process.

Notice: The positioner will start moving.

Arguments:

ID ID of controller

szAxes axes to perform phase finding

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FPL (int *ID*, const char* *szAxes*)**Corresponding command:** FPL

Starts a reference move: Moves all axes *szAxes* synchronously to the positive physical limits of their travel ranges and sets the current positions to the positive range limit values.

Note: Call `PI_IsControllerReady()` to find out if referencing is complete (the controller will be "busy" while referencing, so most other commands will cause a `PI_CONTROLLER_BUSY` error) and `PI_qFRF()` to check whether the reference move was successful.

Arguments:

ID ID of controller

szAxes axes to move

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FRC (int *ID*, const char* *szProcessIdBase*, const char* *szProcessIdsCoupled*)**Corresponding command:** FRC

Fast alignment: Couples fast alignment routines to each other.

Routine types that can be coupled: gradient search routines. Coupled routines are not allowed to stop until all routines coupled to them are finished.

Arguments:

ID ID of controller

szProcessIdBase The identifier of a routine.

szProcessIdsCoupled The identifier of a routine that is to be coupled to the routine given by *szProcessIdBase*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FRF (int *ID*, const char* *szAxes*)**Corresponding command:** FRF

Starts a reference move: Synchronous reference move of all axes *szAxes*, i.e. the given axis is moved to its physical reference point and the current position is set to the reference position.

Note: Call `PI_IsControllerReady()` to find out if referencing is complete (the controller will be "busy" while referencing, so most other commands will cause a `PI_CONTROLLER_BUSY` error) and `PI_qFRF()` to check whether the reference move was successful.

Arguments:

ID ID of controller
szAxes string with axes

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FRP (int *ID*, const char* *szScanRoutineNames*, const int* *piOptionsArray*)**Corresponding command:** FRP

Fast alignment: Stops, pauses or resumes a fast alignment routine. A routine to be stopped or paused must have been started with `PI_FRS` before. A routine to be resumed with `PI_FRP` must have been paused with `PI_FRP` before.

Arguments:

ID ID of controller
szScanRoutineNames The identifier of the routine.
piOptionsArray The action to be performed for the routine. Possible actions:
 0 = stop the routine
 1 = pause the routine
 2 = resume the routine

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FRS (int *ID*, const char* *szScanRoutineNames*)**Corresponding command:** FRS

Fast alignment: Starts a fast alignment routine. The routine must have been defined before with `PI_FDR()` or `PI_FDG()` or via the appropriate parameters (see E712T0016 Technical Note).

Arguments:

ID ID of controller
szScanRoutineNames The identifier of the routine. Multiple gradient search routines can run synchronously for the axes on both the sender and receiver side. They can be coupled to each other with `PI_FRC()`.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_FSA (int *ID*, const char* *szAxis1*, double *dLength1*, const char* *szAxis2*, double *dLength2*, double *dThreshold*, double *dDistance*, double *dAlignStep*, int *iAnalogInput*)**Corresponding command:** FSA

Starts a scanning procedure to determine the maximum intensity of an analog input signal in a plane. The search consists of two subprocedures:

- "Coarse portion"; corresponds to the procedure that is started with the `PI_FSC()` function
- "Fine portion"; corresponds to the procedure that is started with the `PI_AAP()` function

The fine portion is only executed when the coarse portion has previously been successfully completed.

Arguments:**ID** ID of controller**szAxis1** first axis that defines scanning area. Axes X, Y, and Z are permissible. During the coarse portion, the platform is moved in this axis from scanning line to scanning line by the distance given by **dDistance**.**dLength1** length of scanning area along **szAxis1****szAxis2** second axis that defines scanning area. Axes X, Y, and Z are permissible. During the coarse portion, the scanning lines are in this axis.**dLength2** length of scanning area along **szAxis2****dThreshold** intensity threshold of the analog input signal, in V**dDistance** distance between the scanning lines, is only used during the coarse portion**dAlignStep** starting value for the step size, is only used during the fine portion,**iAnalogInput** is the identifier of the analog input signal whose maximum intensity is sought**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FSC (int *ID*, const char* *szAxis1*, double *dLength1*, const char* *szAxis2*, double *dLength2*, double *dThreshold*, double *dDistance*, int *iAnalogInput*)

Corresponding command: FSC

Starts a scanning procedure which scans a specified area ("scanning area") until the analog input signal reaches a specified intensity threshold.

The scanning procedure started with PI_FSC() corresponds to the "coarse portion" of the scanning procedure that is started with the PI_FSA function.

Arguments:**ID** ID of controller**szAxis1** the axis in which the platform moves from scanning line to scanning line by the distance given by **dDistance**.**dLength1** length of scanning area along **szAxis1****szAxis2** is the axis in which the scanning lines are located,**dLength2** length of scanning area along **szAxis2****dThreshold** intensity threshold of the analog input signal, in V**dDistance** distance between the scanning lines**iAnalogInput** is the identifier of the analog input signal whose maximum intensity is sought**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FSF (int *ID*, const char* *szAxis*, double *forceValue1*, double *positionOffset*, **BOOL** *useForceValue2*, double *forceValue2*)

Corresponding command: FSF

Starts a find-surface procedure. A find-surface procedure is recommended for axes that are to be operated in a force control mode. For procedure details, see the controller documentation.

Arguments:**ID** ID of controller**szAxis** string with ID of axis**forceValue1** is a force value as float. Default unit: gF.**positionOffset** distance to be added to the found surface position, as float.**useForceValue2** specifies whether an automatic adaptation of feedforward settings for force control is to be included in the find-surface procedure, **TRUE** for "yes", **FALSE** for "no"**forceValue2** is a force value as float. Default unit: gF. Only used if automatic adaptation of feedforward settings is enabled.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)

BOOL PI_FSM (int *ID*, const char* *szAxis1*, double *dLength1*, const char* *szAxis2*, double *dLength2*, double *dThreshold*, double *dDistance*, int *iAnalogInput*)

Corresponding command: FSM

Starts a scanning procedure to determine the global maximum intensity of an analog input signal in a plane.

Arguments:

ID ID of controller

szAxis1 the axis in which the platform moves from scanning line to scanning line by the distance given by *dDistance*.

dLength1 length of scanning area along *szAxis1*

szAxis2 is the axis in which the scanning lines are located,

dLength2 length of scanning area along *szAxis2*

dThreshold intensity threshold of the analog input signal, in V

dDistance distance between the scanning lines

iAnalogInput is the identifier of the analog input signal whose maximum intensity is sought

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_GetAsyncBuffer (int *ID*, double ***pnValArray*)

Get address of internal buffer used for storing data read in by a call to PI_qDRR(), PI_qDDL(), PI_qGWD(), PI_qTWS(), PI_qJLT() or PI_qHIT().

Arguments:

ID ID of controller

pnValarray pointer to receive address of internal array used to store the data, the DLL will have allocated enough memory to store all data; call **PI_GetAsyncBufferIndex()** to find out how many data points have been transferred up to that time.

Returns:

TRUE if successful, **FALSE** otherwise

int PI_GetAsyncBufferIndex (int *ID*)

Get index used for the internal buffer filled with data read in by a call to PI_qDRR(), PI_qDDL(), PI_qGWD(), PI_qTWS(), PI_qJLT() or PI_qHIT().

Arguments:

ID ID of controller

Returns:

Index of the data element which was last read in, **-1** otherwise

BOOL PI_GetDynamicMoveBufferSize (int *ID*, long* *pnSize*)

Corresponding command: #11

#11 gets the free memory space of a buffer that contains the motion profile points. For more information, see "Motions of the Hexapod" in the controller User Manual.

Arguments:

ID ID of controller

pnSize current number of free motion profile points

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_GOH (int *ID*, const char* *szAxes*)

Corresponding command: GOH

Move all axes in *szAxes* to their home positions (is equivalent to moving the axes to positions 0 using PI_MOV()).

Depending on the controller, the definition of the home position can be changed with PI_DFH().

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are affected.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_HasPosChanged (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: #6

Queries whether the axis positions have changed since the last position query was sent.

Arguments:

ID ID of controller

szAxes axis of controller

pbValueArray indicates whether axis positions have changed, the response is bit-mapped

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_HDT (int *ID*, const int* *iDeviceIDsArray*, const int* *iAxisIDsArray*, const int* *piValueArray*, int *iArraySize*)

Corresponding command: HDT

Assigns a lookup table to the given axis of the given HID device.

Arguments:

ID ID of controller

iDeviceIDsArray HID devices connected to the controller

iAxisIDsArray axes of the HID device(s)

piValueArray lookup tables to be assigned. Supported tables depend on the controller.

Possible tables (ID: type):

1: linear

2: parabolic

3: cubic

4: exponential

5: inverted linear

6: inverted parabolic

101 or higher: user-defined tables

iArraySize size of *iDeviceIDsArray*, *iAxisIDsArray* and *piValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_HIA (int *ID*, const char* *szAxes*, const int* *iFunctionArray*, const int* *iDeviceIDsArray*, const int* *iAxesIDsArray*)

Corresponding command: HIA

Configures the control of axes of the controller by axes of HID devices ("HID control"): Assigns an axis of an HID device to the given motion parameter of the given axis of the controller.

Arguments:

ID ID of controller

szAxes axes of controller

iFunctionArray motion parameters to be controlled by the axes of HID devices

iDeviceIDsArray HID devices connected to the controller

iAxesIDsArray axes of the HID device(s)

Returns:

TRUE if successful, FALSE otherwise

BOOL **PI_HIL** (int *ID*, const int* *iDeviceIDsArray*, const int* *iLED_IDsArray*, const int* *pnValueArray*, int *iArraySize*)

Corresponding command: HIL

Sets the current state of the given output unit or characteristic ("LED") of the given HID device.

Arguments:

ID ID of controller

iDeviceIDsArray HID devices connected to the controller

iLED_IDsArray output units or characteristics ("LEDs") of the HID device(s)

pnValueArray states to be set for the output units or characteristics of the HID device(s)

iArraySize size of *iDeviceIDsArray*, *iLED_IDsArray* and *pnValueArray*

Returns:

TRUE if successful, FALSE otherwise

BOOL **PI_HIN** (int *ID*, const char* *szAxes*, const BOOL* *pbValueArray*)

Corresponding command: HIN

Enables or disables the control by HID devices ("HID control") for the given axis of the controller.

Arguments:

ID ID of controller

szAxes string with axes of the controller

pbValueArray activation state of the HID control for the specified controller axes, TRUE for "enabled", FALSE for "disabled"

Returns:

TRUE if successful, FALSE otherwise

BOOL **PI_HIS** (int *ID*, const int* *iDeviceIDsArray*, const int* *itemIDsArray*, const int* *iPropertyIDArray*, const char* *szValues*, int *iArraySize*)

Corresponding command: HIS

Configures the given HID device.

Arguments:

ID ID of controller

iDeviceIDsArray HID devices connected to the controller

itemIDsArray operating elements of the HID device(s)

iPropertyIDArray properties of the operating elements of the HID device(s)

szValues string with the values to which the properties of the operating elements are to be set

iArraySize size of *iDeviceIDsArray*, *itemIDsArray* and *iPropertyIDArray*

Returns:

TRUE if successful, FALSE otherwise

BOOL **PI_HIT** (int *ID*, const int* *piTableIDsArray*, const int* *piPointNumberArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: HIT

Fills the given lookup table with values.

Arguments:

ID ID of controller
piTableIdsArray lookup tables of the controller
piPointNumberArray points in the lookup table (index begins with 1)
pdValueArray values of the points (range is -1.0 to 1.0)
iArraySize size of *piTableIdsArray*, *piPointNumberArray* and *pdValueArray*

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_HLT (int ID, const char* szAxes)

Corresponding **command**: HLT
 Halt the motion of given axes smoothly.
 Error code 10 is set. PI_HLT() does not stop macros.

Arguments:

ID ID of controller
szAxes string with axes, if "" or NULL all axes are affected.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_IFC (int ID, const char* szParameters, const char* szValues)

Corresponding command: IFC
 Interface configuration.

After PI_IFC() is sent, the new setting becomes active and the host PC interface configuration may need to be changed to maintain communication.

Arguments:

ID ID of controller
szParameters determines which interface <parameter> should be changed. See szValues.
szValues Array with the values of the parameters:
 for **szParameters** = RSBAUD, the **szValues** parameter value gives the baud rate to be used for RS-232 communication
 for **szParameters** = GPADR, the **szValues** parameter value gives the device address to be used for GPIB (IEEE 488) communication
 for **szParameters** = IPADR, the first four portions of the **szValues** parameter value specify the default IP address for TCP/IP communication, the last portion specifies the default port to be used
 for **szParameters** = IPSTART, the **szValues** parameter value defines the startup behavior for configuration of the IP address for TCP/IP communication:
 0 = use IP address defined with IPADR
 1 = use DHCP to obtain IP address, if this fails, use IPADR
 for **szParameters** = IPMASK, the **szValues** parameter value gives the IP mask to be used for TCP/IP communication, in the form uint.uint.uint.uint

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_IFS (int ID, const char* szPassword, const char* szParameters, const char* szValues)

Corresponding command: IFS
 Interface parameter store.

The power-on default parameters for the interface are changed in non-volatile memory, but the current active parameters are not. Settings made with PI_IFS() become active with the next power-on or reboot.

Arguments:

ID ID of controller
szPassword > the default password to write to EPROM is 100.

szParameters determines which interface <parameter> should be changed. See szValues.

szValues Array with the values of the parameters:

- for **szParameters** = RSBAUD, the **szValues** parameter value gives the baud rate to be used for RS-232 communication
- for **szParameters** = GPADR, the **szValues** parameter value gives the device address to be used for GPIB (IEEE 488) communication
- for **szParameters** = IPADR, the first four portions of the **szValues** parameter value specify the default IP address for TCP/IP communication, the last portion specifies the default port to be used
- for **szParameters** = IPSTART, the **szValues** parameter value defines the startup behavior for configuration of the IP address for TCP/IP communication:
 - 0 = use IP address defined with IPADR
 - 1 = use DHCP to obtain IP address, if this fails, use IPADR
- for **szParameters** = IPMASK, the **szValues** parameter value gives the IP mask to be used for TCP/IP communication, in the form uint.uint.uint.uint

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_IMP (int *ID*, const char* *szAxes*, const double* *pdImpulseSize*)

Corresponding command: IMP

Starts performing an impulse and recording the impulse response for the given axis. An "impulse" consists of a relative move of the specified amplitude followed by an equal relative move in the opposite direction.

Arguments:

- ID** ID of controller
- szAxes** axes for which the impulse response will be recorded
- pdImpulseSize** array with the pulse height (amplitude values).

Returns:

TRUE if no error **FALSE** otherwise

BOOL PI_IsAvailable (int *ID*)

Corresponding command: *IDN?

Function checks if the controller is "available" and is ready to respond.

Arguments:

- ID** ID of controller

Returns:

TRUE if controller is available, **FALSE** otherwise (see p. 10)

BOOL PI_IsControllerReady (int *ID*, int * *piControllerReady*)

Corresponding command: #7 (ASCII 7)

Asks controller for ready status (tests if controller is ready to perform a new command).

Arguments:

- ID** ID of controller
- piControllerReady** array to receive the status of the controller: 1 if controller is ready
0 if controller is not ready (e.g. performing a referencing command)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_IsMoving (int *ID*, const char * *szAxes*, BOOL* *pbValueArray*)

Corresponding command: #5 (ASCII 5)

Check if *szAxes* are moving. If an axis is moving the corresponding element of the array will be TRUE, otherwise FALSE. If no axes were specified, only one boolean value is returned and *pbValueArray[0]* will contain a generalized state: TRUE if at least one axis is moving, FALSE if no axis is moving.

Arguments:

ID ID of controller

szAxes string with axes, if "" or NULL all axes are affected.

pbValueArray array to receive the status of the axes

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_IsRunningMacro (int *ID*, BOOL* *pbRunningMacro*)

Corresponding command: #8 (ASCII 8)

Check if controller is currently running a macro

Arguments:

ID ID of controller

pbRunningMacro pointer to boolean to receive answer: TRUE if a macro is running, FALSE otherwise

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_JAX (int *ID*, const int *iJoystickID*, const int *iAxesID*, const char* *szAxesBuffer*)

Corresponding command: JAX

Set axis controlled by a joystick which is directly connected to the controller.

Each axis of the controller can only be controlled by one joystick axis.

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickID joystick device connected to the controller

iAxesID IDs of the joystick axes

szAxesBuffer name(s) of the axis or axes to be controlled by this joystick axis

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_JDT (int *ID*, const int* *iJoystickIDs*, const int* *iAxesIDs*, const int* *piValarray*, int *iArraySize*)

Corresponding command: JDT

Set default lookup table for the given joystick axis of the given joystick which is directly connected to the controller.

The current valid lookup table for the specified joystick axis is overwritten by the selection made with PI_JDT().

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDs array with joystick devices connected to the controller

iAxesIDs array with joystick axis to be set

piValarray pointer to array with table types for the corresponding joystick axes, valid table types are:

1 = linear

2 = parabolic

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_JLT (int *ID*, int *iJoystickID*, int *iAxisID*, int *iStartAddress*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: JLT

Fills the lookup table for the given axis of the given joystick device which is connected to the controller.

Arguments:

ID ID of controller

iJoystickID joystick device connected to the controller

iAxisID joystick axis to be set

iStartAddress index of a point in the lookup table, starts with 1

pdValueArray values of the points in the lookup table

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_JON (int *ID*, const int* *iJoystickIDs*, const BOOL* *pbValarray*, int *iArraySize*)

Corresponding command: JON

Enable or disable a joystick which is directly connected to the controller.

The joystick must be enabled for joystick control of the controller axis which was assigned to the joystick axis with PI_JAX().

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDs array with joystick devices connected to the controller

pbValarray pointer to array with joystick enable states (0 for deactivate, 1 for activate)

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KCP (int *ID*, const char* *szSource*, const char* *szDestination*)

Corresponding command: KCP

Copies a coordinate system.

Arguments:

ID ID of controller

szSource name of already defined coordinate system

szDestination name of coordinate system copy

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KEN (int *ID*, const char* *szNameOfCoordSystem*)

Corresponding command: KEN

Enables an already defined coordinate system.

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be enabled

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KLD (int *ID*, const char* *szNameOfCoordSystem*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: KLD

Defines a levelling coordinate system (KLD type). A coordinate system defined with KLD is intended to eliminate Hexapod misalignment. Use KLD in case misalignment is known via an external measurable deviation.

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

szAxes string with axes

pdValueArray positions (for axes X, Y, Z) and angles (for axes U, V, W)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KLF (int *ID*, const char* *szNameOfCoordSystem*)

Corresponding command: KLF

Defines a levelling coordinate system (KLF type). A coordinate system defined with KLF is intended to eliminate Hexapod misalignment. Use KLF in case the Hexapod is already in the aligned position.

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KLN (int *ID*, const char* *szNameOfChild*, const char* *szNameOfParent*)

Corresponding command: KLN

Links two coordinate systems together by defining a parent-child relation; thus forming a chain.

Arguments:

ID ID of controller

szNameOfChild name of the child coordinate system

szNameOfParent name of the parent coordinate system

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KRM (int *ID*, const char* *szNameOfCoordSystem*)

Corresponding command: KRM

This command deletes a coordinate system

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be deleted

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KSB (int *ID*, const char* *szNameOfCoordSystem*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: KSB

Defines a new coordinate system of KSB type by changing the orientation of the base coordinate system (possible in steps of 90°).

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

szAxes string with axes, possible values are U, V, W

pdValueArray angles in degrees, possible values are 0, 90, 180, 270, -90, -180, -270

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KSD (int *ID*, const char* *szNameOfCoordSystem*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: KSD

This command defines a new KSD type coordinate system. The center of rotation can be changed with the coordinates X, Y, Z. The orientation of the coordinate system can be changed with the coordinates U, V, W.

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

szAxes string with axes

pdValueArray positions (for axes X, Y, Z) and angles (for axes U, V, W)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KSF (int *ID*, const char* *szNameOfCoordSystem*)

Corresponding command: KSF

This command defines a new KSF type coordinate system based on the current position and orientation of the Hexapod platform.

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KST (int *ID*, const char* *szNameOfCoordSystem*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: KST

This command defines a new Tool coordinate system (KST type).

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

szAxes string with axes

pdValueArray positions (for axes X, Y, Z) and angles (for axes U, V, W)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_KSW (int *ID*, const char* *szNameOfCoordSystem*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: KSW

This command defines a new Work coordinate system (KSW type).

Arguments:

ID ID of controller

szNameOfCoordSystem name of the coordinate system to be defined

szAxes string with axes

pdValueArray positions (for axes X, Y, Z) and angles (for axes U, V, W)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_BEG (int *ID*, const char * *szMacroName*)**Corresponding command:** MAC BEG

Put the DLL in macro recording mode. This function sets a flag in the library and effects the operation of other functions. Function will fail if already in recording mode. If successful, the commands that follow become part of the macro, so do not check error state unless **FALSE** is returned. End the recording with **PI_MAC_END()**.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName name under which macro will be stored in the controller

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_DEF (int *ID*, const char * *szMacroName*)**Corresponding command:** MAC DEF

Set macro with name *szMacroName* as start-up macro. This macro will be automatically executed with the next power-on or reboot of the controller. If *szMacroName* is omitted, the current start-up macro selection is canceled. To find out what macros are available call **PI_qMAC()**.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName name of the macro to be the start-up macro

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_DEL (int *ID*, const char * *szMacroName*)**Corresponding command:** MAC DEL

Delete macro with name *szMacroName*. To find out what macros are available call **PI_qMAC()**.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName name of the macro to delete

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_END (int *ID*)**Corresponding command:** MAC END

Take the DLL out of macro recording mode. This function resets a flag in the library and effects the operation of certain other functions. Function will fail if the DLL is not in recording mode.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_NSTART (int *ID*, const char * *szMacroName*, int *nrRuns*)**Corresponding command:** MAC NSTART

Start macro with name *szMacroName*. The macro is repeated *nrRuns* times. To find out what macros are available call PI_qMAC().

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:*ID* ID of controller*szMacroName* string with name of the macro to start*nrRuns* number of runs**Returns:**

TRUE if successful, FALSE otherwise

BOOL PI_MAC_NSTART_Args (int *ID*, const char * *szMacroName*, int *nrRuns*, const char * *szArgs*)**Corresponding command:** MAC NSTART

Start macro with name *szMacroName*. The macro is repeated *nrRuns* times. Another execution is started when the last one is finished.

szArgs stands for the value of a local variable contained in the macro. The sequence of the values in the input must correspond to the numbering of the appropriate local variables, starting with the value of the local variable 1. The individual values must be separated from each other with spaces. A maximum of 256 characters are permitted per function line. *szArgs* can be given directly or via the value of another variable. To find out what macros are available call PI_qMAC().

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:*ID* ID of controller*szMacroName* string with name of the macro to start*nrRuns* number of runs*szArgs* value of a local variable contained in the macro**Returns:**

TRUE if successful, FALSE otherwise

BOOL PI_MAC_qDEF (int *ID*, char * *szBuffer*, int *iBufferSize*)**Corresponding command:** MAC DEF?

Ask for the start-up macro.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:*ID* ID of controller*szBuffer* buffer to receive the string read in from controller, contains the name of the start-up macro.

If no start-up macro is defined, the response is an empty string with the terminating character.

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.**Returns:**

TRUE if successful, FALSE otherwise

BOOL PI_MAC_qERR (int *ID*, char * *szBuffer*, int *iBufferSize*)**Corresponding command:** MAC ERR?

Reports the last error which occurred during macro execution.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:*ID* ID of controller*szBuffer* buffer to receive the string read in from controller, contains the error code number.*iBufferSize* size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise.

BOOL PI_MAC_qFREE (int *ID*, int * *pnFreeSpace*)**Corresponding command:** MAC ERR?

Gets the free memory space for macro recording.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

pnFreeSpace number of characters in bytes for which free memory is still available.

Returns:

TRUE if successful, **FALSE** otherwise.

BOOL PI_MAC_START (int *ID*, const char * *szMacroName*)**Corresponding command:** MAC START

Start macro with name *szMacroName*. To find out what macros are available call PI_qMAC().

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName string with name of the macro to start

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MAC_START_Args (int *ID*, const char * *szMacroName*, const char* *szArgs*)**Corresponding command:** MAC START

Start macro with name *szName*. *szArgs* has the same function as with PI_MAC_NSTART_Args.

To find out what macros are available call PI_qMAC().

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName string with name of the macro to start

szArgs value of a local variable contained in the macro

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_MEX (int *ID*, const char * *szCondition*)**Corresponding command:** MEX

Stop macro execution due to a given condition of the following type: a specified value is compared with a queried value according to a specified rule.

Can only be used in macros.

When the macro interpreter accesses this command the condition is checked. If it is true the current macro is stopped, otherwise macro execution is continued with the next line. Should the condition be fulfilled later, the interpreter will ignore it.

See also PI_WAC().

See "Controller Macros" and the MEX command description in the controller User Manual for details.

Arguments:

ID ID of controller

szCondition string with condition to evaluate

Returns:
TRUE if successful, **FALSE** otherwise

BOOL PI_MOD (int *ID*, const char* *szItems*, const unsigned int * *iModeArray*, const char* *szValues*)

Corresponding command: MOD

Set modes for axes / channels / system.

Arguments:

ID ID of controller

szItems string with item identifiers

iModeArray array with IDs of modes to be set

szValues string with values for each mode to be set

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_MOV (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: MOV

Move *szAxes* to specified absolute positions. Axes will start moving to the new positions if ALL given targets are within the allowed ranges and ALL axes can move. All axes start moving simultaneously. Servo must be enabled for all commanded axes prior to using this command.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray target positions for the axes

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_MRT (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: MRT

Move *szAxes* relative to current position and orientation in Tool coordinate system. Position and orientation of the Tool coordinate system change with each motion of the platform.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray amounts to be added (algebraically) to current target positions of the axes

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_MRW (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: MRW

Move *szAxes* relative to current position and orientation in Work coordinate system. Position and orientation of the Work coordinate system do NOT change with motions of the platform.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray amounts to be added (algebraically) to current target positions of the axes

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_MVE (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: MVE

Set new absolute target positions for given axes. Axes will start moving to the new positions if ALL given targets are within the allowed range and ALL axes can move.

If the affected axes are mounted in a way that they move perpendicular to each other, the combined motion of them will describe a linear path. This is achieved by appropriate calculation of accelerations, velocities and decelerations. The current settings for velocity, acceleration and deceleration define the maximum possible values, and the slowest axis determines the resulting velocities.

All axes start moving simultaneously.

This command can be interrupted by PI_STP() and PI_HLT(). No other motion commands (e.g. PI_MOV(), PI_MVR()) are allowed during vector move.

Servo must be enabled for all commanded axes prior to using this command. If servo is switched off or motion error occurs during motion, all axes are stopped.

Arguments:

ID ID of controller
szAxes string with axes
pdValueArray target positions for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_MVR (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: MVR

Move *szAxes* relative to current target position. The new target position is calculated by adding the given position value to the last commanded target value. Axes will start moving to the new position if ALL given targets are within the allowed range and ALL axes can move. All axes start moving simultaneously. Servo must be enabled for all commanded axes prior to using this command.

Arguments:

ID ID of controller
szAxes string with axes
pdValueArray amounts to be added (algebraically) to current target positions of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_NAV (int *ID*, const int* *piAnalogChannelIds*, const int* *piNrReadingsValues*, int *iArraySize*)

Corresponding command: NAV

Determines the number of readout values of the analog input that are averaged.

Arguments:

ID ID of controller
piAnalogChannelIds identifier of the analog input channel
piNrReadingsValues number of readout values of the analog signal
iArraySize size of arrays *piAnalogChannelIds* and *piNrReadingsValues*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_NLM (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: NLM

Set lower limits ("soft limit") for the positions of *szAxes*.

Depending on the controller, the soft limits are activated and deactivated with PI_SSL().

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray lower limits for position

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_OAC (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*);

Corresponding command: OAC

Set open-loop acceleration of *szAxes*. The PI_OAC setting only takes effect when the given axis is in open-loop operation (servo off).

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels

pdValueArray acceleration value

iArraySize the size of the arrays with the PiezoWalk channels and acceleration values

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_OAD (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: OAD

Open-loop analog driving of the given PiezoWalk channel.

Servo must be disabled for the commanded axis prior to using this command (open-loop operation).

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels

pdValueArray is the feed voltage amplitude in V, see above for details

iArraySize the size of the arrays with the PiezoWalk channels and feed voltages

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_ODC (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*);

Corresponding command: ODC

Set open-loop deceleration of *szAxes*. The PI_ODC setting only takes effect when the given axis is in open-loop operation (servo off).

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels

pdValueArray deceleration value

iArraySize the size of the arrays with the PiezoWalk channels and deceleration values

Returns:

TRUE if successful, **FALSE** otherwise

```
BOOL PI_OMA (int ID, const char* szAxes, const double* pdValueArray);
```

Corresponding command: OMA

Commands *szAxes* to the given absolute position. Motion is realized in open-loop nanostepping mode. Servo must be disabled for the commanded axis prior to using this function (open-loop operation).

With PI_OMA() there is no position control (i.e. the target position is not maintained by any control loop).

Arguments:

ID ID of controller
szAxes string with axes
pdValueArray target positions for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_OMR (int ID, const char* szAxes, const double* pdValueArray);
```

Corresponding command: OMR

Commands *szAxes* to a position relative to the last commanded open-loop target position. The new open-loop target position is calculated by adding the given value *pdValueArray* to the last commanded target value. Motion is realized in nanostepping mode. Servo must be disabled for the commanded axis prior to using this function (open-loop operation). With PI_OMR there is no position control (i.e. the target position is not maintained by a control loop).

Arguments:

ID ID of controller
szAxes string with axes
pdValueArray target positions for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_ONL (int ID, const int* iPiezoChannels, const int* pdValarray, int iArraySize)
```

Corresponding command: ONL

Sets control mode for given piezo channel (ONLINE or OFFLINE mode).

Arguments:

ID ID of controller
iPiezoChannels string with piezo channels
pbValueArray gives the control mode, can have the following values:
 0 = OFFLINE mode, the output voltage depends on analog control input and DC offset applied to the channel
 1 = ONLINE mode, the controller controls the generation of the output voltage
 In ONLINE mode the SERVO switches of all channels must be set to OFF on the piezo control electronics.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_OSM (int ID, const int* piPIEZOWALKChannelsArray, const int* piValueArray, int iArraySize)
```

Corresponding command: OSM

Open-loop step moving of the given PiezoWalk channel.

Prior to using PI_OSM(), servo must be disabled for the axis to which the PiezoWalk channel is assigned (open-loop operation).

Arguments:

ID ID of controller
piPIEZOWALKChannelsArray array with PiezoWalk channels
piValueArray number of steps for the PiezoWalk channels (integer steps only)

iArraySize the size of the arrays with the PiezoWalk channels and number of steps

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_OSMf (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: OSM

Open-loop step moving of the given PiezoWalk channel.

Prior to using PI_OSMf(), servo must be disabled for the axis to which the PiezoWalk channel is assigned (open-loop operation).

PI_OSMf() is identical with PI_OSM() but allows to command parts of a step cycle (floating-point numbers are accepted).

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels

pdValueArray number of steps for the PiezoWalk channels (floating-point numbers)

iArraySize the size of the arrays with the PiezoWalk channels and number of steps

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_OVL (int *ID*, const int* *piPIEZOWALKChannelsArray*, double* *pdValueArray*, int *ArraySize*)

Corresponding command: OVL

Set velocity for open-loop nanostepping motion of given PiezoWalk channel.

The PI_OVL() setting only takes effect when the given axis is in open-loop operation (servo off).

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray Array with PIEZOWALK channels

pdValueArray maximum velocities for the axes

iArraySize number of items in arrays

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_PLM (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: PLM

Set upper limits ("soft limit") for the positions of *szAxes*.

Depending on the controller, the soft limits are activated and deactivated with PI_SSL().

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray upper limits for position

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_POL (int *ID*, const char* *szAxes*, const int* *piValueArray*)

Corresponding command: POL

Set the axis to either 0 % or 100 % of its travel range. It does not use the actuator's previous history but instead, the maximum number of pulses / maximum duration of pulses.

Arguments:

ID ID of controller

szAxes string with axes

piValueArray set axis travel range, **1** for "100%", **0** for "0%"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_POS (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: POS

Set current position for given axis (does not cause motion). An axis is considered as "referenced" when the position was set with PI_POS(), so that PI_qFRF() replies "1". Setting the current position with PI_POS() is only possible when the referencing mode is set to "0", see PI_RON().

NOTICE:

The "software-based" travel range limits (PI_qTMN() and PI_qTMX()) and the "software-based" home position (PI_qDHF()) are not adapted when a position value is set with PI_POS(). This may result in

- target positions which are inside the range limits but can not be reached by the hardware—the mechanics is at the hardstop but tries to move further and must be stopped with PI_STP()
- target positions which can be reached by the hardware but are outside of the range limits—e.g. the mechanics is at the negative hardstop and physically could move to the positive hardstop, but due to the software based-travel range limits the target position is not accepted and no motion is possible
- a home position which is outside of the travel range.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray new axis positions in physical units

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qACC (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: ACC?

Gets the acceleration value set with PI_ACC() for closed-loop operation.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with the acceleration settings of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qAOS (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: AOS?

Get Analog Input Offset, which was set by PI_AOS() or by a parameter command.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with analog offset of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qATC (int *ID*, const int* *piChannels*, int* *piValueArray*, int *iArraySize*)**Corresponding command:** ATC?

Get the options used for the latest auto calibration procedure started with PI_ATC().

See "Calibration Settings" in the User Manual of the controller for more information.

Arguments:*ID* ID of controller*piChannels* string with channels of the piezo control electronics*piValueArray* comprises the settings of the latest auto calibration procedure.*iArraySize* size of arrays**Returns:**

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_qATZ (int *ID*, const char* *szAxes*, int* *piAtzResult*)**Corresponding command:** ATZ?

Reports if the AutoZero procedure called by PI_ATZ() was successful

Arguments:*ID* ID of controller*szAxes* string with axes, if "" or NULL all axes are queried.*piAtzResult* 1 if PI_ATZ was successful performed, 0 if not successful**Returns:**

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_qATS (int *ID*, const int* *piChannels*, const int* *piOptions*, int* *piValueArray*, int *iArraySize*)**Corresponding command:** ATS?

Query the results of the latest auto calibration procedure started with PI_ATC().

See "Calibration Settings" in the User Manual of the controller for more information.

Arguments:*ID* ID of controller*piChannels* string with channels of the piezo control electronics*piOptions* gives the option to be queried. See PI_ATC() for details.*piValueArray* gives the results of the latest auto calibration procedure. If 0, the PI_ATC() procedure was successful. Values >0 indicate option specific error codes; multiple non-zero error codes for the same channel and option will be listed one after another.*iArraySize* size of arrays**Returns:**

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_qBRA (const int *ID*, char * *szBuffer*, const int *maxlen*)**Corresponding command:** BRA?

Gets brake activation state of given axes.

Arguments:*ID* ID of controller*szBuffer* buffer to store the read in string*maxlen* size of *buffer*, must be given to avoid a buffer overflow.**Returns:**

TRUE if successful, FALSE otherwise

BOOL PI_qCAV (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: CAV?

Get the current value of the variable controlled by the selected closed-loop control mode (see PI_CMO() for selection).

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with current values of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCCL (int *ID*, int* *piCommandLevel*)

Corresponding command: CCL?

Returns the current *CommandLevel*.

Arguments:

ID ID of controller

piCommandLevel variable to receive the current command level. See PI_CCL() for possible values.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCCV (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: CCV?

Get currently valid control value.

PI_qCCV() queries the control value in open-loop and closed-loop operation.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with current control values of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCMN (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: CMN?

Get the minimum commandable closed-loop target of *szAxes*. The physical unit and hence the interpretation of the value depend on the closed-loop control mode which is selected for the axis (see PI_CMO() for selection).

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to receive the minimum commandable closed-loop target of the axes in physical units.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCMO (int *ID*, const char* *szAxes*, int* *piValueArray*)

Corresponding command: CMO?

Get the closed-loop control mode which is currently selected for *szAxes*. **Arguments:**

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

piValueArray array to receive modes for the specified axes

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_qCMX (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: CMX?

Get the maximum commandable closed-loop target of *szAxes*. The physical unit and hence the interpretation of the value depend on the closed-loop control mode which is selected for the axis (see PI_CMO() for selection).

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pdValueArray array to receive the maximum commandable closed-loop target of the axes in physical units.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCOV (int *ID*, const int* *piChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: COV?

Get current open-loop velocity

Arguments:

ID ID of controller

piChannelsArray is an array with the channels to be queried

pdValueArray array to receive the values

iArraySize is the size of the array **pdValueArray**

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCST (int *ID*, const char* *szAxes*, char* *szNames*, int *iBufferSize*)

Corresponding command: CST?

Get the type names of the positioners associated with *szAxes*. The individual names are preceded by the one-character axis identifier followed by "=" the positioner name and a "\n" (line-feed). The line-feed is preceded by a space on every line except the last.

Arguments:

ID ID of controller

szAxes identifiers of the axes, if "" or **NULL** all axes are queried

szNames buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of *szNames*, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qCSV (int *ID*, double* *pdCommandSyntaxVersion*)

Corresponding command: CSV?

Returns the current *CommandSyntaxVersion*.

Arguments:

ID ID of controller

pdCommandSyntaxVersion variable to receive the current command syntax version (2.0 for GCS 2.0).

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_qCTI (int ID, const int* piTriggerInputIds, const int*
piTriggerParameterArray, char* szValueArray, int iArraySize, int iBufferSize)

```

Corresponding command: CTI?

Get the trigger input configuration for the given trigger input line.

Arguments:

ID ID of controller

piTriggerInputIds is an array with the trigger input lines of the controller

piTriggerParameterArray is an array with the CTI parameter IDs

szValueArray buffer to receive the values to which the CTI parameters are set, each line has a value of a single CTI parameter, lines are separated by '\n' ("line-feed")

iArraySize is the size of the array *piTriggerInputIds*

iBufferSize size of *szValueArray*, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_qCTO (int ID, const int* piTriggerOutputIds, const int*
piTriggerParameterArray, double* pdValueArray, int iArraySize)

```

Corresponding command: CTO?

Get the trigger output configuration for the given trigger output line.

Arguments:

ID ID of controller

piTriggerOutputIds is an array with the trigger output lines of the controller

piTriggerParameterArray is an array with the CTO parameter IDs

pdValueArray buffer to receive the values to which the CTO parameters are set

iArraySize is the size of the array *piTriggerOutputIds*

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_qCTOString (int ID, const int* piTriggerOutputIds, const int*
piTriggerParameterArray, char* szValueArray, int iArraySize, int iBufferSize)

```

Corresponding command: CTO?

Get the trigger output configuration for the given trigger output line.

Arguments:

ID ID of controller

piTriggerOutputIds is an array with the trigger output lines of the controller

piTriggerParameterArray is an array with the CTO parameter IDs

szValueArray buffer to receive the values to which the CTO parameters are set, each line has a value of a single CTO parameter, lines are separated by '\n' ("line-feed")

iArraySize is the size of the array *piTriggerOutputIds*

iBufferSize size of *szValueArray*, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

```

BOOL PI_qCTV (int ID, const char* szAxes, double* pdValueArray)

```

Corresponding command: CTV?

Get the currently valid closed-loop target for *szAxes*. The physical unit and hence the interpretation of the value depend on the closed-loop control mode which is selected for the axis (see PI_CMO() for selection).

Use PI_qCAV() to get the current value of the controlled variable.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with target values of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDCO (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: DCO?

Gets drift compensation mode of *szAxes*

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pbValueArray array to receive the drift compensation modes of the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDEC (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: DEC?

Gets the deceleration value for closed-loop operation set with PI_DEC().

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with the deceleration settings of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDFH (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: DFH?

Returns the sensor positions the current home position definitions of *szAxes* are based on.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to receive the sensor positions that were valid when PI_DFH() was called the last time (are used as offsets for the calculation of the current axis positions)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDIO (int *ID*, const long* *piChannelsArray*, BOOL* *pbValueArray*, int *iArraySize*)

Corresponding command: DIO?

Returns the states of the specified digital input channels.

Use PI_qTIO() (p. 96) to get the number of installed digital I/O channels.

Arguments:

ID ID of controller

piChannelsArray array containing digital output channel identifiers

pbValueArray array containing the states of specified digital output channels, **TRUE** if HIGH, **FALSE** if LOW

Depending on the controller, *piChannelsArray* can contain 0. In this case, the array is a bit pattern which gives the states of all lines.

iArraySize the size of *piChannelsArray* and *pbValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDRC (int *ID*, const int* *piRecordTableIdsArray*, char* *szRecordSourceIds*, int* *piRecordOptionArray*, int *iRecordSourceIdsBufferSize*, int *iRecordOptionArraySize*)

Corresponding command: DRC?

Returns the data recorder configuration for the queried record table. The configuration can be changed with PI_DRC(). The recorded data can be read with PI_qDRR().

Trigger options for recording can be set with PI_DRT() and read with PI_qDRT().

Arguments:

ID ID of controller

piRecordTableIdsArray array of the record table IDs.

szRecordSourceIds array to receive the record source (for example axis number or channel number. The meaning of this value depends on the corresponding record option).

piRecordOptionsArray array to receive the record option, i.e. the kind of data to be recorded

iRecordSourceIdsBufferSize size of *szRecordSourceIds*, must be given to avoid a buffer overflow

iRecordOptionArraySize size of *piRecordTableIdsArray* and *piRecordOptionsArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDRL (int *ID*, const int* *piRecordTableIdsArray*, int* *piNumberOfRecordedValuesArray*, int *iArraySize*)

Corresponding command: DRL?

Reads the number of points comprised by the last recording, i.e. the number of values that have been recorded since data recording was last triggered. This way it is possible to find out if recording has been finished (all desired points are in the record table) or to find out how many points can be currently read from the record table. Depending on the controller, reading more points than the number returned by PI_qDRL can also read old record table content.

Arguments:

ID ID of controller

piRecordTableIdsArray array of the record channel IDs

piNumberOfRecordedValuesArray array to receive the number of values that have been recorded since recording was last triggered or PI_DRC() was called for the record channel

iArraySize the size of the arrays *piRecordTableIdsArray*, *piNumberOfRecordedValuesArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDRR (int *ID*, const int* *piRecTableIdsArray*, int *iNumberOfRecTables*, int *iOffsetOfFirstPointInRecordTable*, int *iNumberOfValues*, double** *pdValueArray*, char* *szGcsArrayHeader*, int *iGcsArrayHeaderMaxSize*)

Corresponding command: DRR?

Read data record tables. This function reads the data asynchronously, it will return as soon as the data header has been read and start a background process which reads in the data itself. See PI_GetAsyncBuffer() and PI_GetAsyncBufferIndex(). Detailed information about the data read in can be found in the header sent by the controller. See the GCS Array manual for details.

It is possible to read the data while recording is still in progress.

The data is stored on the controller only until a new recording is done or the controller is powered down.

For more information see "Data Recorder" in the controller User Manual.

Arguments:

ID ID of controller

piRecTableIdArray IDs of data record tables

iNumberOfRecTables number of record tables to read
iOffsetOfFirstPointInRecordTable index of first value to be read (starts with index 1)
iNumberOfValues number of values to read
pdValarray pointer to internal array to store the data; data from all tables read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call ***PI_GetAsyncBufferIndex()*** to find out how many data points have already been transferred
szGcsArrayHeader buffer to store the GCS array header
iGcsArrayHeaderMaxSize size of the buffer to store the GCS Array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

BOOL *PI_qDRR_SYNC* (int *ID*, int *iRecordTableId*, int *iOffsetOfFirstPointInRecordTable*, int *iNumberOfValues*, double* *pdValueArray*)

Corresponding command: DRR?

Returns the data points of the last recorded data set.

It is possible to read the data while recording is still in progress.

The data is stored on the controller only until a new recording is done or the controller is powered down.

For detailed information see "Data Recorder" in the controller User Manual.

Arguments:

ID ID of controller

iRecordTableId Id of the record table.

iOffsetOfFirstPointInRecordTable The start point in the specified record table (starts with index 1)

iNumberOfValues The number of values to read.

pdValueArray array to receive the values

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL *PI_qDRT* (int *ID*, const int* *piRecordTableIdsArray*, int* *piTriggerSourceArray*, char* *szValues*, int *iArraySize*, int *iValueBufferLength*)

Corresponding command: DRT?

Returns the current trigger source setting for the given data recorder table.

Arguments:

ID ID of controller

piRecordTableIdsArray array of the record table IDs

piTriggerSourceArray array to receive the trigger source

szValues buffer to receive the trigger-source-dependent value

iArraySize size of *piRecordTableIdsArray* and *piTriggerSourceArray*

iValueBufferLength size of *szValues*, must be given to prevent buffer overflow

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL *PI_qEAX* (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: EAX?

Get enable status of axes: enabled/not enabled.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray enable status for the specified axes, **TRUE** for "enabled", **FALSE** for "not enabled"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qECO (int *ID*, const char* *szSendString*, char* *szValues*, int *iBufferSize*)

Corresponding command: ECO?

Returns a string. PI_qECO() can be used to test the communication.

Arguments:

ID ID of controller

szSendString array of any given combination of characters consisting of letters and numbers

szValues buffer to receive the string read in from controller

iBufferSize size of *szValues*

Returns:

TRUE if query successful, **FALSE** otherwise

BOOL PI_qERR (int *ID*, long* *pnError*)

Corresponding command: ERR?

Get the error state of the controller. Because the DLL may have queried (and cleared) controller error conditions on its own, it is safer to call PI_GetError() which will first check the internal error state of the library. For a list of possible error codes see p. 136.

Arguments:

ID ID of controller

pnError integer to receive error code of the controller

Returns:

TRUE if query successful, **FALSE** otherwise

BOOL PI_qFGC(int *ID*, const char* *szProcessIds*, double* *pdScanAxisCenterValueArray*, double* *pdStepAxisCenterValueArray*)

Corresponding command: FGC?

Fast alignment: Gets the current center position of the circular motion of a gradient search routine.

Arguments:

ID ID of controller

szProcessIds The identifier of the routine.

pdScanAxisCenterValueArray Current center position of the circular motion for the scan axis

pdStepAxisCenterValueArray Current center position of the circular motion for the step axis

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qFPH (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: FPH?

Gets found phase (offset between motor and encoder) for *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray array to receive the phase offsets found for the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qFRC (int *ID*, const char* *szProcessIdsBase*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: FRC?

Fast alignment: Gets coupled fast alignment routines.

Arguments:

ID ID of controller

szProcessIdBase The identifier of the routine to be queried.

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed").
Contains the identifiers of routines that are coupled to the routine given by *szProcessIdBase*.

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qFRF (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: FRF?

Indicates whether the given axis is referenced or not.

An axis is considered as "referenced" when the current position value is set to a known position.

Depending on the controller, this is the case if a reference move was successfully executed with PI_FRF(), PI_FNL() or PI_FPL(), or if the position was set manually with PI_POS().

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are affected.

pbValueArray array to receive, 1 if successful, 0 if axis is not referenced (e.g. referencing move failed or has not finished yet)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qFRH (int *ID*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: FRH?

Fast alignment: Lists descriptions and physical units for the routine results that can be queried with PI_qFRR().

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qFRP (int *ID*, const char* *szScanRoutineNames*, int* *piOptionsArray*)

Corresponding command: FRP?

Fast alignment: Gets the current state of a fast alignment routine.

Arguments:

ID ID of controller

szScanRoutineNames The identifier of the routine.

piOptionsArray is the current state of the routine. Possible states:

0 = routine has been stopped / is not running

1 = routine has been paused

2 = routine is running

If no routine ID is given, the state of all routines is returned.

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_qFRR (int *ID*, const char* *szScanRoutineNames*, const unsigned int* *iResultIdsArray*, char* *szResult*, int *iBufferSize*)

Corresponding command: FRR?

Fast alignment: Gets the results of a fast alignment routine. See the E712T0016 Technical Note for valid result identifiers and possible results. Use the response to PI_qFRH() to get information on the supported result identifiers.

Arguments:

ID ID of controller

szScanRoutineNames The identifier of the routine. If no routine identifier is given, all available results are queried.

iResultIdsArray The identifier of the result. If no result identifier is given, all available results for the given routine are queried.

szResult buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of szBuffer, must be given to avoid buffer overflow.")

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qFSF (int *ID*, const char* *szAxes*, double* *forceValue1Array*, double* *positionOffsetArray*, double* *forceValue2Array*)

Corresponding command: FSF?

Gets the settings made with PI_FSF() for the find-surface procedure.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

forceValue1Array array to receive the configured forceValue1 of the specified axes

positionOffsetArray array to receive the configured position offset of the specified axes

forceValue2Array array to receive the configured forceValue2 of the specified axes

Returns:

TRUE if no error, **FALSE** otherwise

BOOL PI_qFSR (int *ID*, const char* *szAxes*, **BOOL*** *pbValueArray*)

Corresponding command: FSR?

Gets the result of the find-surface procedure initiated with PI_FSF().

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pbValueArray array to receive the results of the specified axes, **TRUE** for "successful", **FALSE** for "procedure failed or still running"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qFSS (int *ID*, int* *piResult*)

Corresponding command: FSS?

Gets the status of the last scanning procedure that was started.

In order to check whether a scanning procedure is still going on, the motion status of the axes can be queried with PI_IsMoving().

PI_qFSS() gets the status of scanning procedures that are started with the following commands:

PI_AAP(), PI_FIO(), PI_FLM(), PI_FLS(), PI_FSA(), PI_FSC(), PI_FSM()

Arguments:

ID ID of controller

piResult indicates the status of the last scanning procedure that was started.

1: Scanning procedure has been successfully completed

0: Scanning procedure is still going on or has been unsuccessfully completed.

Returns:

TRUE if successful, FALSE otherwise (see p. 10)

BOOL PI_qHAR (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: HAR?

Gets whether the hard stops of the axis can be used for reference moves.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray indicates whether the axis can be referenced using the hard stop (= 1) or not (= 0).

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_qHDR (int *ID*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: HDR?

Lists a help string which contains all information available for data recording (record options and trigger options, information about additional parameters and commands regarding data recording).

For more information see "Data Recorder" in the controller User Manual.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_qHDT (int *ID*, const int* *iDeviceIDsArray*, const int* *iAxisIDsArray*, int* *piValueArray*, int *iArraySize*)

Corresponding command: HDT?

Gets the currently assigned lookup table for the given axis of the given HID device.

Arguments:

ID ID of controller

iDeviceIDsArray HID devices connected to the controller.

iAxisIDsArray axes of the HID device(s)

piValueArray lookup tables assigned to the axes of the HID device(s), see PI_HDT() for available tables

iArraySize size of *iDeviceIDsArray*, *iAxisIDsArray* and *piValueArray*

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_qHIA (int *ID*, const char* *szAxes*, const int* *iFunctionArray*, int* *iDeviceIDsArray*, int* *iAxesIDsArray*)

Corresponding command: HIA?

Gets the current control configuration for the given motion parameter of the given axis of the controller, i. e. the currently assigned axis of an HID device.

Arguments:

ID ID of controller

szAxes string with axes of the controller
iFunctionArray motion parameters to be queried
iDeviceIDsArray IDs of the HID devices used for HID control
iAxesIDsArray IDs of the axes of the HID device(s) used for HID control

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHIB (int *ID*, const int* *iDeviceIDsArray*, const int* *iButtonIDsArray*, int* *pbValueArray*, int *iArraySize*)

Corresponding command: HIB?

Gets the current state of the given button of the given HID device.

Arguments:

ID ID of controller
iDeviceIDsArray HID devices connected to the controller
iButtonIDsArray buttons of the HID device(s)
pbValueArray array to receive the states of the buttons
iArraySize size of *iDeviceIDsArray*, *iButtonIDsArray* and *pbValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHIE (int *ID*, const int* *iDeviceIDsArray*, const int* *iAxesIDsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: HIE?

Gets the current displacement of the given axis of the given HID device.

Arguments:

ID ID of controller
iDeviceIDsArray HID devices connected to the controller
iAxesIDsArray axes of the HID device(s)
pdValueArray array to receive the displacement of the axes of the HID device(s)
iArraySize size of *iDeviceIDsArray*, *iAxesIDsArray* and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHIL (int *ID*, const int* *iDeviceIDsArray*, const int* *iLED_IDsArray*, int* *pnValueArray*, int *iArraySize*)

Corresponding command: HIL?

Gets the current state of the given output unit or characteristic ("LED") of the given HID device.

Arguments:

ID ID of controller
iDeviceIDsArray HID devices connected to the controller
iLED_IDsArray output units or characteristics ("LEDs") of the HID device(s)
pnValueArray array to receive the states of the LEDs
iArraySize size of *iDeviceIDsArray*, *iLED_IDsArray* and *pnValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHIN (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: HIN?

Gets the activation state of the control by HID devices ("HID control") for the given axis of the controller.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray array to receive the activation state of the HID control

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHIS (int *ID*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: HIS?

Gets the properties of the operating elements of HID devices connected to the controller.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise

BOOL PI_qHIT (int *ID*, const int* *piTableIdsArray*, int *iNumberOfTables*, int *iOffsetOfFirstPointInTable*, int *iNumberOfValues*, double** *pdValueArray*, char* *szGcsArrayHeader*, int *iGcsArrayHeaderMaxSize*)

Corresponding command: HIT?

Gets the values of the given points in the given lookup table.

Arguments:

ID ID of controller

piTableIdsArray IDs of the lookup tables of the controller

iNumberOfTables number of tables to read

iOffsetOfFirstPointInTable index of first point to be read (starts with index 1)

iNumberOfValues number of points to read

pdValueArray pointer to internal array to store the data; data from all tables read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call *PI_GetAsyncBufferIndex()* to find out how many data points have already been transferred

szGcsArrayHeader buffer to store the GCS array header

iGcsArrayHeaderMaxSize size of the buffer to store the GCS array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qHLP (int *ID*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: HLP?

Read in the help string from the controller. The answer is quite long (up to 3000 characters) so be sure to provide enough space! (And you may have to wait a bit...)

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qHPA (int *ID*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: HPA?

Lists a help string which contains all available parameters with short descriptions. See the user manual of the controller for an appropriate list of all parameters available for your controller.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed")

iBufferSize size of **szBuffer**, must be given to avoid buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qHPV (int ID, char* szBuffer, int iBufferSize)**Corresponding command:** HPV?

Responds with a help string which contains possible parameters values. Use PI_qHPA instead to get a help string which contains all available parameters with short descriptions.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed").

iBufferSize size of **szBuffer**, must be given to avoid buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qIDN (int ID, char* szBuffer, int iBufferSize)**Corresponding command:** *IDN?

Get identification string of the controller.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller

iBufferSize size of **szBuffer**, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qIFC (int ID, const char* szParameters, char* szBuffer, int iBufferSize)**Corresponding command:** IFC?

Get the interface configuration from volatile memory.

Arguments:

ID ID of controller

szParameters the interface parameter to be queried, can be RSBAUD, GPADR, IPADR, IPSTART, IPMASK and MACADR (depends on the controller)

szBuffer Buffer to receive the values of the parameters from volatile memory

iBufferSize the size of the buffer **szBuffer**

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qIFS (int ID, const char* szParameters, char* szBuffer, int iBufferSize)**Corresponding command:** IFS?

Get the interface configuration stored in non-volatile memory (this is the current power-on default).

Arguments:

ID ID of controller

szParameters the interface parameters to be queried, can be RSBAUD, GPADR, IPADR, IPSTART, IPMASK and MACADR (depends on the controller)

szBuffer buffer to receive the values of the parameters from non-volatile memory

iBufferSize size of **szBuffer**, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qIMP (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: IMP?

Get last sent impulse parameters for given axis (sent with PI_IMP()).

Arguments:

ID ID of controller

szAxes axis for which the impulse parameters are to be read

pdValueArray Array to be filled with impulse parameters of the axes; currently only the pulse height.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qJAS (int *ID*, const int* *iJoystickIDsArray*, const int* *iAxesIDsArray*, double* *pdValarray*, int *iArraySize*)

Corresponding command: JAS?

Get the current status of the given axis of the given joystick device which is directly connected to the controller. The reported factor is applied to the velocity set with PI_VEL() (closed-loop operation) or PI_OVL() (open-loop operation), the range is -1.0 to 1.0.

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDsArray array with joystick devices connected to the controller

iAxesDsArray array with joystick axes

pdValarray pointer to array to receive the joystick axis amplitude, i.e. the factor which is currently applied to the current valid velocity setting of the controlled motion axis; corresponds to the current displacement of the joystick axis.

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qJAX (int *ID*, const int* *iJoystickIDsArray*, const int* *iAxesIDsArray*, int *iArraySize*, char* *szAxesBuffer*, int *iBufferSize*)

Corresponding command: JAX?

Get axis controlled by a joystick axis of a joystick device which is directly connected to the controller.

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDsArray array with joystick devices connected to the controller

iAxesIDsArray array with IDs of the joystick axes

iArraySize size of arrays

buffer buffer to receive the string read in from controller; will contain axis IDs of axes associated with corresponding joystick axis

maxlen size of *buffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qJBS (int ID, const int* iJoystickIDsArray, const int* iButtonIDsArray,
BOOL* pbValarray, int iArraySize)

```

Corresponding command: JBS?

Get the current status of the given button of the given joystick device which is directly connected to the controller.

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDsArray array with joystick devices connected to the controller

iButtonIDsArray array with joystick buttons

pbValarray pointer to array to receive the joystick button state, indicates if the joystick button is pressed; 0 = not pressed, 1 = pressed

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qJLT (int ID, const int* iJoystickIDsArray, const int* iAxisIDsArray, int
iNumberOfTables, int iOffsetOfFirstPointInTable, int iNumberOfValues, double**
pdValueArray, char* szGcsArrayHeader, int iGcsArrayHeaderMaxSize)

```

Corresponding command: JLT?

Get joystick lookup table values.

Arguments:

ID ID of controller

szAxes string with axes

iJoystickIDsArray array with joystick devices connected to the controller

iAxisIDsArray array with joystick axes

iNumberOfTables number of tables to read

iOffsetOfFirstPointInTable index of first point to be read (starts with index 1)

iNumberOfValues number of points to read

pdValueArray pointer to internal array to store the data; data from all tables read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call `PI_GetAsyncBufferIndex()` to find out how many data points have already been transferred

szGcsArrayHeader buffer to store the GCS array header

iGcsArrayHeaderMaxSize size of the buffer to store the GCS array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qJON (int ID, const int* iJoystickIDsArray, BOOL* pbValarray, int
iArraySize)

```

Corresponding command: JON?

Get activation state of the given joystick device which is directly connected to the controller.

See "Joystick Control" in the controller User Manual for details.

Arguments:

ID ID of controller

iJoystickIDsArray array with joystick devices connected to the controller

pbValarray pointer to array to receive the joystick enable states (0 for deactivated, 1 for activated)

iArraySize size of arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qLST (int *ID*, char* *buffer*, int *bufsize*)

Corresponding command: LST?

Lists names of data files in nonvolatile memory.

Arguments:

ID ID of controller

buffer buffer to receive list names of data files

bufsize must be given to avoid a buffer overflow

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qKEN (int *ID*, const char* *szNamesOfCoordSystems*, char* *buffer*, int *bufsize*)

Corresponding command: KEN?

Lists enabled coordinate systems by name.

Arguments:

ID ID of controller

szNamesOfCoordSystems string with name of the coordinate system. Can be NULL or "" to return all

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qKET (int *ID*, const char* *szNamesOfCoordSystems*, char* *buffer*, int *bufsize*)

Corresponding command: KET?

Lists enabled coordinate systems by type.

Arguments:

ID ID of controller

szNamesOfCoordSystems string with name of the coordinate system. Can be NULL or "" to return all

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qKLC (int *ID*, const char* *szNamesOfCoordSystem1*, const char* *szNamesOfCoordSystem2*, const char* *szItem1*, const char* *szItem2*, char* *buffer*, int *bufsize*)

Corresponding command: KLC?

Lists properties of combinations of Work and Tool coordinate systems.

Arguments:

ID ID of controller

szNamesOfCoordSystem1 string with name of the coordinate system. Can be NULL or ""

szNamesOfCoordSystem2 string with name of the coordinate system. Can be NULL or ""

szItem1 string with first item to query. Can be NULL or ""

szItem2 string with second item to query. Can be NULL or ""

Buffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qKLN (int *ID*, const char* *szNamesOfCoordSystems*, char* *buffer*, int *bufsize*)

Corresponding command: KLN?

Lists coordinate system chains.

Arguments:

ID ID of controller

szNamesOfCoordSystems string with name of the coordinate system. Can be NULL or "" to return all

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_qKLS (int *ID*, const char* *szNamesOfCoordSystem*, const char* *szItem1*, const char* *szItem2*, char* *buffer*, int *bufsize*)

Corresponding command: KLS?

Lists properties of all coordinate systems..

Arguments:

ID ID of controller

szNamesOfCoordSystem string with name of the coordinate system. Can be NULL or ""

szItem1 string with first item to query. Can be NULL or ""

szItem2 string with second item to query. Can be NULL or ""

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_qKLT (int *ID*, const char* *szStartCoordSystem*, const char* *szEndCoordSystem*, char* *buffer*, int *bufsize*)

Corresponding command: KLT?

Returns the position and orientation of the coordinate system which results from a chain of linked coordinate systems, or from a part of a chain. The part to be queried can be limited by specifying the start and end points in the chain.

Arguments:

ID ID of controller

szStartCoordSystem name of the coordinate system which is the start point in the chain. Can be NULL or ""

szEndCoordSystem name of the coordinate system which is the end point in the chain. Can be NULL or ""

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_qLIM (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: LIM?

Check if the given axes have limit switches.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pbValueArray array for limit switch info: **TRUE** if axis has limit switches, **FALSE** if not

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qMAC (int *ID*, const char* *szMacroName*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: MAC?

Get available macros, or list contents of a specific macro. If *szMacroName* is empty or **NULL**, all available macros are listed in *szBuffer*, separated with line-feed characters. Otherwise the content of the macro with name *szMacroName* is listed, the single lines separated by line-feed characters. If there are no macros stored or the requested macro is empty the answer will be "".

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szMacroName string with name of the macro to list

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qMAN (int *ID*, const char* *szCommand*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: MAN?

Shows a detailed help text for individual commands.

Arguments:

ID ID of controller

szCommand is the command mnemonic of the command for which the help text is to be displayed.

szBuffer buffer to receive the string that describes the command.

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qMOD (int *ID*, const char* *szItems*, const unsigned int * *iModeArray*, char* *szValues*, int *iMaxValueSize*)

Corresponding command: MOD?

Get modes for axes / channels / system.

Arguments:

ID ID of controller

szItems string with item identifiers

iModeArray array with IDs of modes to be queried

szValues string to be filled with values for each mode

iMaxValueSize size of *szValues*, must be given to avoid buffer overflow

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qMOV (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: MOV?

Read the commanded target positions for *szAxes*. Use PI_qPOS() to get the current positions.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with target positions of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qNAV (int *ID*, const int* *piAnalogChannelIds*, int* *piNrReadingsValues*, int *iArraySize*)

Corresponding command: NAV?

Gets the number of readout values of the analog input used for averaging.

The response consists of a line feed when the controller does not contain an analog input channel.

Arguments:

ID ID of controller

piAnalogChannelIds array of analog input channel identifiers

piNrReadingsValues array to be filled with number of readout values used for averaging

iArraySize size of *piAnalogChannelIds* and *piNrReadingsValues*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qNLM (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: NLM?

Get lower limits ("soft limits") for the positions of *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray array to be filled with lower limits for position of the axes.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qOAC (int *ID*, const int* *piPIEZOWALKChannelsArray*, double* *pdValueArray*, int *iArraySize*);

Corresponding command: OAC?

Get current open-loop acceleration of the PiezoWalk channels.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels, if **NULL** all PiezoWalk channels are queried

pdValueArray array to receive the acceleration value

iArraySize size of the arrays *piPIEZOWALKChannelsArray* (if not **NULL**) and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qOAD (int *ID*, const int* *piPIEZOWALKChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: OAD?

Reads last commanded open-loop analog driving voltage of given PiezoWalk channel.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels, if **NULL** all PiezoWalk channels are queried.

pdValueArray array to receive the last-commanded feed voltage amplitude in V
iArraySize size of the arrays *piPIEZOWALKChannelsArray* (if not **NULL**) and *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_qODC (int ID, const int* piPIEZOWALKChannelsArray, double*
pdValueArray, int iArraySize);
```

Corresponding command: ODC?

Get current open-loop deceleration of the PiezoWalk channels.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels, if **NULL** all PiezoWalk channels are queried

pdValueArray array to receive the acceleration value

iArraySize size of the arrays *piPIEZOWALKChannelsArray* (if not **NULL**) and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

```
BOOL PI_qOMA (int ID, const char* szAxes, double* pdValueArray);
```

Corresponding command: OMA?

Reads last commanded open-loop target *pdValueArray* of given *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with target positions of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_qONL (int ID, const int* iPiezoChannels, int* pdValarray, int iArraySize)
```

Corresponding command: ONL?

Gets current control mode for *iPiezoChannels*.

Arguments:

ID ID of controller

iPiezoChannels string with piezo channels, if "" or **NULL** all piezo channels are queried

pbValueArray array to receive the control modes of the specified piezo channels, **TRUE** for "ONLINE", **FALSE** for "OFFLINE"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```
BOOL PI_qONT (int ID, const char* szAxes, BOOL* pbValueArray)
```

Corresponding command: ONT?

Check if *szAxes* have reached the target.

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray array to be filled with current on-target state of the axes

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qOSN (int ID, const int* piPiezoWalkChannelsArray, double*
pdValueArray, int iArraySize)

```

Corresponding command: OSN?

Reads the number of steps still to be performed for the given PiezoWalk channel after the last call of PI_OSM().

Arguments:

ID ID of controller

piPiezoWalkChannelsArray array with PiezoWalk channels, if **NULL** all PiezoWalk channels are queried.

pdValueArray array to receive the number of steps which are still to be performed for open-loop step moving of the given PiezoWalk channels

iArraySize size of the arrays *piPiezoWalkChannelsArray* (if not **NULL**) and *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_qOVF (int ID, const char* szAxes, BOOL* pbOverflow)

```

Corresponding command: OVF?

Checks overflow status of *szAxes*. Overflow means that the control variables are out of range (can only happen if controller is in closed-loop mode).

Arguments:

ID ID of controller

szAxes string with axes

pbOverflow array to be filled with current overflow status of the axes ("0" = axis is not in overflow or "1" = axis is in overflow)

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qOVL (int ID, const int* piPIEZOWALKChannelsArray, double*
pdValueArray, int iArraySize)

```

Corresponding command: OVL?

Get the current value of the velocity for open-loop nanostepping motion.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channel identifiers

pdValueArray array to be filled with the current active velocity values for open-loop nanostepping motion, in steps/s

iArraySize size of arrays

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_qPLM (int ID, const char* szAxes, double* pdValueArray)

```

Corresponding command: PLM?

Get upper limits ("soft limit") for the positions of *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray array to be filled with upper limits for position of the axes.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qPOS (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: POS?

Get the current positions of *szAxes*. If no position sensor is present in your system, the response to PI_qPOS() is not meaningful.

To request the current position of input signal channels (sensors) in physical units, use PI_qTSP() instead.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to receive the current positions of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qPUN (int *ID*, const char* *szAxes*, char* *szUnit*, int *iBufferSize*)

Corresponding command: PUN?

Get the position units of *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to receive the position units of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qRMC (int *ID*, char * *szBuffer*, int *iBufferSize*)

Corresponding command: RMC?

List macros which are currently running.

See "Controller Macros" and the MAC command description in the controller User Manual for details.

Arguments:

ID ID of controller

szBuffer buffer to receive the string read in from controller, lines are separated by line-feed characters. Contains the names of the macros which are saved on the controller and currently running. The response is an empty line when no macro is running.

iBufferSize size of *buffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qRON (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: RON?

Gets reference mode for given axes.

Arguments:

ID ID of controller

szAxes string with axes

pbValarray array to receive reference modes for the specified axes

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qRTD (int *ID*, int *tableType*, int *tableID*, int *infoID*, char* *buffer*, int *bufsize*)

Corresponding command: RTD?

Reads the content of a data table in volatile memory.

Before reading, the content must be loaded into the volatile memory from a data file with PI_RTD(), *tableType* = 100, *tableID* = 100. For details, see PI_RTD() (p. 103).

Arguments:*ID* ID of controller*tableType* is the type of the table from which the data is to be read*tableID* is the identifier of the table from which the data is to be read.*infoID* is the identifier of the information to be read*buffer* buffer to receive data table*bufsize* must be given to avoid a buffer overflow**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_qRTO** (int *ID*, const char* *szAxes*, int* *pbValueArray*)**Corresponding command:** RTO?

Read the "ready-for-turn-off state" of the given axis (check whether PI_RTO() was successful).

Arguments:*ID* ID of controller*szAxes* string with axes, if "" or **NULL** all axes are affected.*pbValueArray* array to receive, 1 if ready (i.e. PI_RTO() was successful), 0 if not ready (i.e. PI_RTO() was not successful)**Returns:****TRUE** if successful, **FALSE** otherwise**BOOL PI_qRTR** (int *ID*, int* *piRecordTableRate*)**Corresponding command:** RTR?

Gets the current record table rate, i.e. the number of servo-loop cycles used in data recording operations.

Arguments:*ID* ID of controller*piRecordTableRate* variable to be filled with the record table rate**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_qSAI** (int *ID*, char* *szAxes*, int *iBufferSize*)**Corresponding command:** SAI?

Get the identifiers for all configured axes. Each character in the returned string is an axis identifier for one logical axis.

Deactivated axes are not shown.

Arguments:*ID* ID of controller*szAxes* buffer to receive the string read in*iBufferSize* size of *szAxes*, must be given to avoid a buffer overflow.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_qSAI_ALL** (int *ID*, char* *szAxes*, int *iBufferSize*)**Corresponding command:** SAI?

Get the identifiers for all axes (configured and unconfigured axes). Each character in the returned string is an axis identifier for one logical axis. This function is provided for compatibility with controllers which allow for axis deactivation. PI_qSAI_ALL() then ensures that the answer also includes the axes which are "deactivated".

Arguments:*ID* ID of controller

szAxes buffer to receive the string read in
iBufferSize size of **szAxes**, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSCT (int *ID*, double* *pdCycleTime*)

Corresponding command: SCT?

Gets the current cycle time for running a defined motion profile.

Arguments:

ID ID of controller

pdCycleTime cycle time in ms

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSEP (int *ID*, const char* *szAxes*, const int* *piParameterArray*, double* *pdValueArray*, char* *szStrings*, int *iMaximumStringSize*)

Corresponding command: SEP?

Query specified parameters for **szAxes** from non-volatile memory. For each desired parameter you must specify a designator in **szAxes** and the parameter ID in the corresponding element of *piParameterArray*. See the user manual of the controller for a list of the available parameters.

Arguments:

ID ID of controller

szAxes string with designator, one parameter is read for each designatorID in **szAxes**

piParameterArray parameter IDs

pdValueArray array to receive the values of the requested parameters

szStrings string to receive the with linefeed-separated parameter values; when not needed set to **NULL** (i.e. if numeric parameter values are queried)

iMaximumStringSize size of **szStrings**, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSGA (int *ID*, const int* *piAnalogChannelIds*, int* *piGainValues*, int *iArraySize*)

Corresponding command: SGA?

Gets the gain value *piGainValues* for the given analog input channel *piAnalogChannelIds*.

The response consists of a line feed when the controller does not contain an optical analog input channel.

Arguments:

ID ID of controller

piAnalogChannelIds identifier of the analog input channel

piGainValues array to be filled with gain factor values

iArraySize size of *piAnalogChannelIds* and *piGainValues*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSIC (int *ID*, const int* *piFastAlignmentInputIdsArray*, int *iNumberOfInputIds*, char* *szBuffer*, int *iBufferSize*)

Corresponding command: SIC?

Fast alignment: Gets the calculation settings for the given fast alignment input channel.

The calculation results can be queried with PI_qTCI().

See the E712T0016 Technical Note ("Fast Alignment Routines") for detailed descriptions of the fast alignment input channels.

Arguments:

ID ID of controller

piFastAlignmentInputIdsArray The identifier of a fast alignment input channel of the controller.

iNumberOfInputIds size of *piFastAlignmentInputIdsArray*

szBuffer buffer to receive the string read in from controller, lines are separated by '\n' ("line-feed").

iBufferSize size of *szBuffer*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qSMO (int *ID*, char *const *szAxes*, int * *pnValueArray*)

Corresponding command: SMO?

Gets last valid control value of *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are affected.

pnValueArray control values for the specified axes. In servo-on mode the current value, set by the controller, is reported. In servo-off mode the value set by PI_SMO() is reported.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qSPA (int *ID*, const char* *szAxes*, unsigned int* *piParameterArray*, double* *pdValueArray*, char* *szStrings*, int *iMaxNameSize*)

Corresponding command: SPA?

Query specified parameters for *szAxes* from RAM. For each desired parameter you must specify a designator in *szAxes* and the parameter ID in the corresponding element of *iParameterArray*. See the user manual of the controller for a list of the available parameters.

Arguments:

ID ID of controller

szAxes string with designator, one parameter is read for each designator in *szAxes*

piParameterArray parameter IDs

pdValueArray array to be filled with the values of the requested parameters

szStrings string to receive the linefeed-separated parameter values; when not needed set to **NULL** (i.e. if numeric parameter values are queried)

iMaxNameSize size of *szStrings*, must be given to avoid a buffer overflow.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSPI (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: SPI?

Gets the pivot point coordinates in the volatile memory.

Arguments:

ID ID of controller

szAxes can be R, S and T. X, Y and Z can also be used as alias identifiers for R, S and T

pdValueArray value array of the pivot point coordinates in physical units

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSRG (int *ID*, char *const *szAxes*, int * *iRegisterarray*, int * *iValarray*)

Corresponding command: SRG?

Returns register values for queried axes and register numbers.

Arguments:

ID ID of controller

szAxes axis for which the register values should be read

iRegisterarray IDs of registers

iValarray array to be filled with the values for the registers. The answer is bit-mapped and returned as the sum of the individual codes, in hexadecimal format.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qSSA (int *ID*, const int* *iPIEZOWALKChannels*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: SSA?

Get the current value of the voltage amplitude used for nanostepping motion.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray array with PiezoWalk channels

pdValueArray array to be filled with the current active voltage amplitude values in V

iArraySize size of the arrays *piPIEZOWALKChannelsArray* and *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSSL (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: SSL?

Gets the state of the soft limits that are set with PI_NLM() and PI_PLM(). If all arguments are omitted, the state is queried for all axes.

Arguments:

ID ID of controller

szAxes axes of the controller

pbValueArray array to receive the state of the soft limits:

0 = soft limits deactivated

1 = soft limits activated

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSSN (int *ID*, char* *szSerialNumber*, int *iBufferSize*)

Corresponding command: SSN?

Get serial number of the controller.

Arguments:

ID ID of controller

szSerialNumber buffer for storing the string read in

iBufferSize size of buffer, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qSST (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: SST?

Gets the distance ("step size") for motions of the given axis that are triggered by a manual control unit.

Arguments:

ID ID of controller

szAxes axes of the controller, if "" or **NULL** all axes are queried.

pdValueArray array to receive the distance values used for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSTE (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: STE?

Get last sent amplitude for the step response measurement for given axis (sent with PI_STE()).

Arguments:

ID ID of controller

szAxes axes to be read

pdValueArray array to be filled with the step amplitude values of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSVA (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: SVA?

Returns last valid open-loop control value for *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pdValueArray array to be filled with the last commanded open-loop control values (dimensionless).

The interpretation of the open-loop control values depends on the controller.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qSVO (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: SVO?

Get the servo-control mode for *szAxes*

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pbValueArray array to receive the servo modes of the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTAC (int *ID*, int* *piNrChannels*)

Corresponding command: TAC?

Get the number of installed analog channels.

Arguments:

ID ID of controller

piNrChannels pointer to int to receive the number of installed analog channels

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTAD (int *ID*, const int* *piSensorChannelsArray*, int* *piValueArray*, int *iArraySize*)

Corresponding command: TAD?

Returns ADC value for the given input signal channel, without filtering, linearization and transformation.

The response consists of a line feed when the controller does not contain an analog input channel.

Arguments:

ID ID of controller

piSensorChannelsArray array with input signal channels, if **NULL** all channels are queried.

pdValueArray array to receive ADC value (dimensionless)

iArraySize size of the arrays *pdValueArray* and *piSensorChannelsArray* (if not **NULL**)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTAV (int *ID*, const int* *piChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: TAV?

Returns voltage value for the specified analog input channel.

The response consists of a line feed when the controller does not contain an analog input channel.

Arguments:

ID ID of controller

piChannelsArray string with channels. If "" or **NULL** all analog input channels are queried.

pdValueArray array to receive voltage value (in volts)

iArraySize size of *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTCI (int *ID*, const int* *piFastAlignmentInputIDsArray*, double* *pdCalculatedInputValueArray*, int *iArraySize*)

Corresponding command: TCI?

Fast alignment: Gets calculated value of given fast alignment input channel.

The calculation settings of a fast alignment input channel can be defined with PI_SIC() and queried with PI_qSIC().

See the E712T0016 Technical Note ("Fast Alignment Routines") for detailed descriptions of the fast alignment input channels.

Arguments:

ID ID of controller

piFastAlignmentInputIDsArray The identifier of a fast alignment input channel of the controller.

pdCalculatedInputValueArray The current value of the calculated input.

iArraySize size of *pdCalculatedInputValueArray*

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTCV (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: TCV?

Gets the current value of the velocity for closed-loop operation (value calculated by the profile generator).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray array to be filled with the current velocity values calculated by the profile generator

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTGL (int *ID*, const int* *piTrajectoriesArray*, int* *iTrajectorySizesArray*, int *iArraySize*)

Corresponding command: TGL?

Command for motion paths: Queries the number of points in the buffer of the specified trajectory.

For further information, see "Trajectories for Motion Paths" and the description of the TGL? command in the documentation of your controller.

Arguments:

ID ID of controller

piTrajectoriesArray Array with identifiers of the trajectories

iTrajectorySizesArray Array with the current number of points in the buffer of the trajectories

iArraySize number of trajectories

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTGT (int *ID*, const int* *iTrajectoryTiming*)

Corresponding command: TGT?

Command for motion paths: Queries the timing for trajectories. The returned value is valid for all trajectories.

For further information, see "Trajectories for Motion Paths" and the description of the TGT? command in the documentation of your controller.

Arguments:

ID ID of controller

iTrajectoryTiming Time interval between the output of the individual points of a trajectory (unit: Number of servo cycles)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTIO (int *ID*, int* *piInputNr*, int* *piOutputNr*)

Corresponding command: TIO?

Returns the number of available digital I/O channels.

Arguments:

ID ID of controller

piInputNr variable to receive number of available digital input channels

piOutputNr variable to receive number of available digital output channels

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTMN (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: TMN?

Get the low end of the travel range of *szAxes*

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to receive low end of the travel range of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTMX (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: TMX?

Get the high end of the travel range of *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried

pdValueArray array to receive high end of travel range of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTNR (int *ID*, int* *piNumberOfRecordTables*)

Corresponding command: TNR?

Returns the number of data recorder tables.

For more information see "Data Recorder" in the controller User Manual.

Arguments:

ID ID of controller

piNumberOfRecordTables variable to receive number of data recorder tables

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTNS (int *ID*, const int* *piSensorChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: TNS?

Returns normalized value for the specified input signal channel.

Arguments:

ID ID of controller

piSensorChannelsArray array with input signal channels, if **NULL** all channels are queried.

pdValueArray array to receive normalized value (dimensionless)

iArraySize the size of the arrays *pdValueArray* and *piSensorChannelsArray* (if not **NULL**)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTPC (int *ID*, int* *piNumberOfPiezoChannels*)

Corresponding command: TPC?

Get the number of output signal channels available on the controller.

Arguments:

ID ID of controller

piNumberOfPiezoChannels variable to receive number of available output signal channels

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTRA (int *ID*, const char* *szAxes*, const double* *pdComponents*, double* *pdValueArray*)

Corresponding command: TRA?

This command returns the maximum absolute position which can be reached from the current position in the given direction for the queried axis vector.

Arguments:

ID ID of controller
szAxes string with axes
pdComponents components of the vector
pdValueArray array to receive maximum positions of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTRI (int *ID*, const int* *piTriggerInputIds*, BOOL* *pbTriggerState*, int *iArraySize*)

Corresponding command: TRI?

Returns if the trigger input configuration made with PI_CTI() is enabled or disabled for the given digital input line.

Arguments:

ID ID of controller
piTriggerInputIds digital input lines of the controller
pbTriggerState the current states of the digital input lines:
 FALSE = Trigger input disabled
 TRUE = Trigger input enabled
iArraySize size of the arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTRO (int *ID*, const int* *piTriggerOutputIds*, BOOL* *pbTriggerState*, int *iArraySize*)

Corresponding command: TRO?

Returns if the trigger output configuration made with PI_CTO() is enabled or disabled for the given digital output line.

Arguments:

ID ID of controller
piTriggerOutputIds digital output lines of the controller
pbTriggerState the current states of the digital output lines:
 FALSE = Trigger output disabled
 TRUE = Trigger output enabled
iArraySize size of the arrays

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTRS (int *ID*, const char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: TRS?

Ask if *szAxes* have reference sensors with direction sensing.

Arguments:

ID ID of controller
szAxes string with axes, if "" or **NULL** all axes are queried.
pbValueArray array for reference sensor info: **TRUE** if axis has a reference sensor with direction sensing, **FALSE** if not

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qTSC (int *ID*, int* *piNumberOfSensorChannels*)

Corresponding command: TSC?

Get the number of input signal channels available on the controller.

Arguments:

ID ID of controller

piNumberOfSensorChannels variable to receive number of input signal channels

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTSP (int *ID*, const int* *piSensorChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: TSP?

Requests the current position of the given input signal channel in physical units (µm).

Arguments:

ID ID of controller

piSensorChannelsArray array with input signal channels, if **NULL** all channels are queried.

pdValueArray array to receive channel position (in µm)

iArraySize the size of the arrays *pdValueArray* and *piSensorChannelsArray* (if not **NULL**)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTVI (int *ID*, char * *szBuffer*, int *iBufferSize*)

Corresponding GCS command: TVI?

Get valid characters for axes. Each character in the returned string is a valid axis identifier that can be used to "name" an axis with PI_SAI().

Arguments:

ID ID of controller

szBuffer buffer to store the read in string

iBuffer size of *szBuffer*, must be given to avoid a buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qVAR (int *ID*, const char * *szVariables*, char* *szValues*, int *iBufferSize*)

Corresponding command: VAR?

Gets variable value.

If PI_qVAR is combined with PI_CPY(), PI_JRC(), PI_MEX() or PI_WAC(), the response to PI_qVAR() has to be a single value and not more.

More information regarding local and global variables can be found in "Variables" in the controller User Manual.

Arguments:

ID ID of controller

szVariables name of the variable to be queried

szValues is the value to which the variable is set

iBufferSize size of *szVariables* and *szValues*, must be given to avoid buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise.

BOOL PI_qVCO (int *ID*, char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: VCO?

Get the velocity-control mode for *szAxes*

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray array to be filled with the velocity-control modes of the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qVEL (int *ID*, const char* *szAxes*, double* *pdValueArray*)

Corresponding command: VEL?

Gets the velocity value commanded with PI_VEL() for *szAxes*.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are queried.

pdValueArray array to be filled with the velocity settings of the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qVER (int *ID*, char* *szVersion*, int *iBufferSize*)

Corresponding command: VER?

Reports the versions of the controller firmware and the underlying drivers and libraries.

Arguments:

ID ID of controller

szVersion buffer for storing the string read in

iBufferSize size of *szVersion*, must be given to avoid buffer overflow.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qVLS (int *ID*, double* *pdSystemVelocity*)

Corresponding command: VLS?

Gets the velocity of the moving platform of the Hexapod that is set with PI_VLS().

Arguments:

ID ID of controller

pdSystemVelocity velocity value in physical units

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qVMA (int *ID*, const int* *piPiezoChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: VMA?

Get upper piezo voltage soft limit for *piPiezoChannelsArray*.

Arguments:

ID ID of controller

piPiezoChannelsArray array with piezo channels, if **NULL** all piezo channels are queried.

pdValueArray array to be filled with the upper limits for the piezo voltage

iArraySize size of the arrays *pdValueArray* and *piPiezoChannelsArray* (if not **NULL**)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qVMI (int *ID*, const int* *piPiezoChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: VMI?

Get lower piezo voltage soft limit for *piPiezoChannelsArray*.

Arguments:

ID ID of controller

piPiezoChannelsArray array with piezo channels, if **NULL** all piezo channels are queried

pdValueArray array to be filled with the lower limits for the piezo voltage

iArraySize size of the arrays *pdValueArray* and *piPiezoChannelsArray* (if not **NULL**)

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qVMO (int *ID*, const char* *szAxes*, const double* *pdValarray*, **BOOL*** *pbMovePossible*)

Corresponding command: VMO?

Checks whether the moving platform of the Hexapod can approach a specified position from the current position.

PI_qVMO() does not trigger any motion.

Arguments:

ID ID of controller

szAxes string with axes

pdValarray array of target positions

pbMovePossible value to receive, indicates whether the moving platform can approach the position resulting from the given target position values:

0 = specified position cannot be approached

1 = specified position can be approached

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qVOL (int *ID*, const int* *piPiezoChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: VOL?

Get current piezo voltages for *piPiezoChannelsArray*.

Arguments:

ID ID of controller

piPiezoChannelsArray array with channels, if **NULL** all channels are queried

pdValueArray array to be filled with the current voltages for the channels

iArraySize size of the arrays *pdValueArray* and *piPiezoChannelsArray* (if not **NULL**)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qVST (int *ID*, char * *szBuffer*, int *iBufferSize*)

Corresponding command: VST?

Get the names of the available positioner types. The available positioners are read from positioner database(s).

The positioner types listed with PI_qVST() can be assigned to the axes of the controller with PI_CST().

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Note that the assignment of a positioner type with PI_CST() is only permissible for axes A and B. The behavior of the PI_qVST() and PI_CST() functions differs depending on the current versions of the controller firmware and PI GCS 2 DLL. For further details, see p. 135.

Arguments:

ID ID of controller

szBuffer buffer for storing the string read in, lines are separated by \n (line feed)

iBufferSize size of *szBuffer*, must be given to avoid a buffer overflow.

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_RBT (int *ID*)

Corresponding command: RBT

Reboot Controller. Controller behaves like after a cold start.

Arguments:

ID ID of controller

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_RNP (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: RNP

"Relax" the piezos of a given PiezoWalk channel without motion.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray string with PiezoWalk channels

pdValueArray voltages which must be applied for the PiezoWalk channels, must be 0 to set the voltages to 0 V

iArraySize size of the arrays *pdValueArray* and *piPIEZOWALKChannelsArray*

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_RON (const int *ID*, char *const *szAxes*, BOOL * *pbValarray*)

Corresponding command: RON

Sets referencing mode for given axes. Determines how to reference axes measured by incremental sensors.

Arguments:

ID ID of controller

szAxes string with axes

pbValarray reference modes for the specified axes:

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_RPA (int *ID*, const char* *szAxes*, const int* *piParameterArray*)**Corresponding command:** RPA

Copy specified parameters for *szAxes* from the non-volatile memory and write them to RAM. For each desired parameter you must specify a designator in *szAxes*, and the parameter ID in the corresponding element of *piParameterArray*. See the user manual of the controller for a list of available parameters.

Arguments:

ID ID of controller

szAxes string with designators, one parameter is copied for each designator in *szAxes*

piParameterArray parameter IDs

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_RTD (int *ID*, int *tableType*, int *tableID*, const char* *name*)**Corresponding command:** RTD

Reads the content of a data file in nonvolatile memory and writes it to a given table in volatile memory.

Arguments:

ID ID of controller

tableType is the type of the table to which the data is to be written

tableID is the identifier of the table to which the data is to be written

name is the file name

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_RTO (int *ID*, const char* *szAxes*)**Corresponding command:** RTO

Make ready to turn off: The current position of the given axis is written to the non-volatile memory of the controller. Especially for systems which use incremental sensors. Check with PI_qRTO if PI_RTO() was successful.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are affected.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_RTR (int *ID*, int *iRecordTableRate*)**Corresponding command:** RTR

Sets the record table rate, i.e. the number of servo-loop cycles to be used in data recording operations. Settings larger than 1 make it possible to cover longer time periods with a limited number of points.

For more information see "Data Recorder" in the controller User Manual

Arguments:

ID ID of controller

iRecordTableRate is the record table rate to be used (unit: number of servo-loop cycles), must be larger than zero

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SAI (int *ID*, char *const *szOldAxes*, char *const *szNewAxes*)

Corresponding command: SAI

Rename axes: *szOldAxes* will be set to *szNewAxes*. The characters in *szNewAxes* must not be in use for any other existing axes and must each be one of the valid identifiers. All characters in *szNewAxes* will be converted to uppercase letters. Only the **last** occurrence of an axis identifier in *szNewAxes* will be used to change the name.

Arguments:

ID ID of controller
szOldAxes old axis identifiers
szNewAxes new identifiers for the axes

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_SCT (int *ID*, double *dCycleTime*)

Corresponding command: SCT

Determines the cycle time for running a motion profile.

Arguments:

ID ID of controller
dCycleTime cycle time in ms

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SEP (int *ID*, const char* *szPassword*, const char* *szAxes*, const int* *piParameterArray*, const double* *pdValueArray*, const char* *szStrings*)

Corresponding command: SEP

Set specified parameters for *szAxes* in non-volatile memory. For each parameter you must specify a designator in *szAxes*, and the parameter ID in the corresponding element of *piParameterArray*. See the user manual of the controller for a list of available parameters.

Notes:

If the same designator has the same parameter number more than once, only the **last** value will be set. For example PI_SEP(id, "100", "111", {0x1, 0x1, 0x2}, {3e-2, 2e-2, 2e-4}) will set the P-term of '1' to 2e-2 and the I-term to 2e-4.

After parameters were set with PI_SEP(), use PI_RPA() to activate them (write them to volatile memory), or they become active after next power-on or reboot.

Warnings:

This command is for setting hardware-specific parameters. Wrong values may lead to improper operation or damage of your hardware!

The number of write times of non-volatile memory is limited. Do not write parameter values except when necessary.

Arguments:

ID ID of controller
szPassword There is a password required to set parameters in the non-volatile memory. This password is "100"
szAxes string with designators, one parameter is set for each designator in *szAxes*
piParameterArray Parameter IDs
pdValueArray array with the values for the respective parameters
szStrings string with linefeed-separated parameter values; when not needed set to **NULL** (i.e. if numeric parameter values are used)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SGA (int *ID*, const int* *piAnalogChannelIds*, const int* *piGainValues*, int *iArraySize*)

Corresponding command: SGA

Determines the gain value for the given analog input channel.

Arguments:

ID ID of controller

piAnalogChannelIds array of analog input channel identifiers

piGainValues array of gain factors

iArraySize size of *piAnalogChannelIds* and *piGainValues*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SIC (int *ID*, int *iFastAlignmentInputId*, int *iCalcType*, const double* *pdParameters*, int *iNumberOfParameters*)

Corresponding command: SIC

Fast alignment: Defines calculation settings for the given fast alignment input channel.

The current valid calculation settings can be queried with PI_qSIC(). The calculation results can be queried with PI_qTCI().

See the E712T0016 Technical Note ("Fast Alignment Routines") for detailed descriptions.

Arguments:

ID ID of controller

iFastAlignmentInputId The identifier of a fast alignment input channel of the controller.

iCalcType The type of calculation to be applied, can be:

0 = No calculation

1 = Exponential calculation

2 = Polynomial calculation

pdParameters The settings for the selected calculation type.

iNumberOfParameters size of *pdParameters*.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_SMO (int *ID*, char *const *szAxes*, int * *pnValueArray*)

Corresponding command: SMO

Sets control value directly to move the axis. Profile generator (if present), sensor feedback and servo algorithm are not taken into account. This is only possible if servo-control is OFF (see PI_SVO()).

NOTICE: In the case of large control values, the positioner can strike the hard stop despite the limit switch function. This can cause damage to equipment.

Arguments:

ID ID of controller

szAxes string with axes

pnValueArray array with control values.

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_SPA (int *ID*, const char* *szAxes*, const unsigned int* *piParameterArray*, const double* *pdValueArray*, const char* *szStrings*)

Corresponding command: SPA

Set specified parameters for *szAxes* in RAM. For each parameter you must specify a designator in *szAxes*, and the parameter ID in the corresponding element of *iParameterArray*. See the user manual of the controller for a list of available parameters.

Notes:

If the same designator has the same parameter number more than once, only the **last** value will be set. For example `PI_SPA(id, "111", {0x1, 0x1, 0x2}, {3e-2, 2e-2, 2e-4})` will set the P-term of '1' to 2e-2 and the I-term to 2e-4.

Warning:

This command is for setting hardware-specific parameters. Wrong values may lead to improper operation or damage of your hardware!

Arguments:

ID ID of controller

szAxes string with designators, one parameter is set for each designator in *szAxes*

piParameterArray Parameter IDs

pdValueArray array to receive with the values for the respective parameters

szStrings string, with linefeed-separated parameter values; when not needed set to **NULL** (i.e. if numeric parameter values are used)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SPI (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: SPI

Sets the pivot point coordinates in the volatile memory.

Arguments:

ID ID of controller

szAxes can be R, S and T. X, Y and Z can also be used as alias identifiers for R, S and T

pdValueArray value array of the pivot point coordinates

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SSA (int *ID*, const int* *piPIEZOWALKChannelsArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: SSA

Set the voltage amplitude for nanostepping motion of given PiezoWalk channel.

Arguments:

ID ID of controller

piPIEZOWALKChannelsArray string with PiezoWalk channels

pdValueArray the voltage amplitude for nanostepping motion, in V

iArraySize the size of the arrays *piPIEZOWALKChannelsArray* and *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SSL (int *ID*, const char* *szAxes*, const BOOL* *pbValueArray*)

Corresponding command: SSL

Activates or deactivates the soft limits that are set with `PI_NLM()` and `PI_PLM()`. Soft limits can only be activated/deactivated when the axis is not moving (query with `PI_IsMoving()`).

Arguments:

ID ID of controller

szAxes axes of the controller

pbValueArray array with the states of the soft limits:

0 = soft limits deactivated

1 = soft limits activated

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SST (int *ID*, const char* *szAxes*, const double* *pdValueArray*)**Corresponding command:** SST

Sets the distance ("step size") for motions of the given axis that are triggered by a manual control unit.

Arguments:*ID* ID of controller*szAxes* axes of the controller*pdValueArray* value array of the distance values**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_STD** (int *ID*, int *tableType*, int *tableID*, const char* *data*)**Corresponding command:** STD

Save Table Data. Saves the content of a given table from volatile memory to a data file in nonvolatile memory.

With header tables, PI_STD() is also used to write the information in the table before it is saved to data file in nonvolatile memory.

Arguments:*ID* ID of controller*tableType* represents the type of the table whose data is to be saved*tableID* is the identifier of the table whose data is to be saved*data* for all table types, the string is a file name of max. 32 characters. Spaces are not allowed.**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_STE** (int *ID*, const char* *szAxes*, const double* *pdStepSize*)**Corresponding command:** STE

Starts performing a step and recording the step response for the given axis.

Arguments:*ID* ID of controller*szAxes* axes for which the step response will be recorded*pdStepSize* amplitude of the step**Returns:****TRUE** if no error, **FALSE** otherwise (see p. 10)**BOOL PI_StopAll** (int *ID*)**Corresponding command:** #24

Stops the motion of all axes instantaneously. Sets error code to 10. This function is identical in function to PI_STP(), but only one character is sent via the interface.

Arguments:*ID* ID of controller**Returns:****TRUE** if successful, **FALSE** otherwise (see p. 10)

BOOL PI_STP (int *ID*)**Corresponding command:** STP

Stops the motion of all axes instantaneously. Sets error code to 10.

PI_STP() also stops macros.

After the axes are stopped, their target positions are set to their current positions.

Arguments:

ID ID of controller

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_SVA (int *ID*, const char* *szAxes*, double* *pdValueArray*)**Corresponding command:** SVA

Set absolute open-loop control value to move *szAxes*.

Servo must be switched off (open-loop operation) when using this command.

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray absolute open-loop control value

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SVO (int *ID*, const char* *szAxes*, const BOOL* *pbValueArray*)**Corresponding command:** SVO

Set servo-control "on" or "off" (closed-loop/open-loop mode).

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray servo modes for the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_SVR (int *ID*, const char* *szAxes*, double* *pdValueArray*)**Corresponding command:** SVR

Set open-loop control value relative to the current open-loop control value to move *szAxes*.

The new open-loop control value is calculated by adding the given value to the last commanded open-loop control value.

Servo must be switched off when using this command (open-loop operation).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray the open-loop control values which are added to the current values

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TGA (int *ID*, const int* *piTrajectoriesArray*, const double* *pdValarray*, int *iArraySize*)**Corresponding command:** TGA

Command for motion paths: Loads trajectory points to the buffer of the specified trajectory.

Before a trajectory is executed, at least 4 points must be loaded to the trajectory buffer. The maximum number of points in the trajectory buffer is determined by the **Maximum Buffer Size** parameter (0x22000020).

NOTICE:

The controller does not calculate a dynamics profile during the execution of a trajectory. After the last trajectory point has been reached, the motion of the axis is abruptly stopped. This holds true for the proper completion of trajectories as well as for their cancellation (e. g., by a stop command or error). Acceleration / deceleration, velocity, and steadiness of the motion therefore depend on the following factors during trajectory execution:

- Values of the trajectory points
- Timing for the trajectories
- Sufficiently fast refilling of the trajectory buffer

The execution of an unsuitable trajectory can cause the positioner to oscillate or the motion to abruptly stop. Oscillations or abrupt stopping can damage the positioner and/or the load affixed to it. Therefore, observe the following when working with trajectories:

- The path that is specified by the trajectory points must be continuously differentiable at least twice.
- During the execution of the trajectory, the maximum permissible velocity and acceleration of the axis must not be exceeded.
- During the execution of the trajectory, an abrupt stop must not damage the load on the positioner.
- To generate the trajectory points and continuously transfer them to the controller during the trajectory execution, it is recommended to use a suitable program.

For further information, see "Trajectories for Motion Paths" and the description of the TGA command in the documentation of your controller.

Arguments:

ID ID of controller

piTrajectoriesArray array with the identifiers of the trajectories

pdValarray array with the values in FLOAT format; indicates a trajectory point as the absolute position in physical units

iArraySize number of trajectories

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TGC (int *ID*, const int* *piTrajectoriesArray*, int *iArraySize*)

Corresponding command: TGC

Command for motion paths: Deletes the trajectory points in the buffer of the specified trajectory.

For further information, see "Trajectories for Motion Paths" and the description of the TGC command in the documentation of your controller.

Arguments:

ID ID of controller

piTrajectoriesArray array with the identifiers of the trajectories

iArraySize number of trajectories

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TGF (int *ID*, const int* *piTrajectoriesArray*, int *iArraySize*)

Corresponding command: TGF

Command for motion paths: Completes the execution of the specified trajectory

PI_TGF() must be called after the last trajectory point has been loaded. If the trajectory execution is not properly completed with PI_TGF(), an error will occur when the number of points in the buffer falls below the required minimum (4).

A trajectory will only be executed as long as there are at least 4 points in the trajectory buffer. For trajectories to be executed to the end, this command must be sent after all trajectory points have been loaded. It signals to the firmware that no more points will be supplied for the specified trajectory. In this

case, the remaining trajectory points will be processed without an error occurring when the minimum number of points is no longer present.

For further information, see "Trajectories for Motion Paths" and the description of the TGF command in the documentation of your controller.

Arguments:

ID ID of controller

piTrajectoriesArray array with the identifiers of the trajectories

iArraySize number of trajectories

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TGS (int *ID*, const int* *piTrajectoriesArray*, int *iArraySize*)

Corresponding command: TGS

Command for motion paths: Starts the execution of the specified trajectory or trajectories.

Before a trajectory is executed, at least 4 points must be loaded to the trajectory buffer with PI_TGA(). During the execution of a trajectory, the buffer must be refilled fast enough. The execution of a trajectory must be completed with PI_TGF().

For further information, see "Trajectories for Motion Paths" and the description of the TGS command in the documentation of your controller.

Arguments:

ID ID of controller

piTrajectoriesArray array with the identifiers of the trajectories

iArraySize number of trajectories

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TGT (int *ID*, int *iTrajectoryTiming*)

Corresponding command: TGT

Command for motion paths: Sets the timing for trajectories.

The timing specifies the time interval at which the individual points are output during the execution of the trajectories.

The specified value is valid for all trajectories.

NOTICE:

The controller does not calculate a dynamics profile during the execution of a trajectory. After the last trajectory point has been reached, the motion of the axis is abruptly stopped. This holds true for the proper completion of trajectories as well as for their cancellation (e. g., by a stop command or error). Acceleration / deceleration, velocity, and steadiness of the motion therefore depend on the following factors during trajectory execution:

- Values of the trajectory points
- Timing for the trajectories
- Sufficiently fast refilling of the trajectory buffer

The execution of an unsuitable trajectory can cause the positioner to oscillate or the motion to abruptly stop. Oscillations or abrupt stopping can damage the positioner and/or the load affixed to it. Therefore, observe the following when working with trajectories:

- The path that is specified by the trajectory points must be continuously differentiable at least twice.
- During the execution of the trajectory, the maximum permissible velocity and acceleration of the axis must not be exceeded.
- During the execution of the trajectory, an abrupt stop must not damage the load on the positioner.
- To generate the trajectory points and continuously transfer them to the controller during the trajectory execution, it is recommended to use a suitable program.

For further information, see "Trajectories for Motion Paths" and the description of the TGT command in the documentation of your controller.

Arguments:

ID ID of controller

iTrajectoryTiming Time interval between the output of the individual points of a trajectory (unit: Number of servo cycles)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TRI (int *ID*, const int* *piTriggerInputIds*, const BOOL* *pbTriggerState*, int *iArraySize*)

Corresponding command: TRI

Enables or disables the trigger input mode which was set with PI_CTI() for the given digital input line.

Arguments:

ID ID of controller

piTriggerInputIds is an array with the digital input lines of the controller.

pbTriggerState pointer to boolean array with modes for the specified trigger lines, **TRUE** for "on", **FALSE** for "off"

iArraySize number of trigger lines

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_TRO (int *ID*, const int* *piTriggerOutputIds*, const BOOL* *pbTriggerState*, int *iArraySize*)

Corresponding command: TRO

Enables or disables the trigger output mode which was set with PI_CTO() for the given digital output line.

Arguments:

ID ID of controller

piTriggerOutputIds is an array with the digital output lines of the controller.

pbTriggerState pointer to boolean array with modes for the specified trigger lines, **TRUE** for "on", **FALSE** for "off"

iArraySize number of trigger lines

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_TSP (int *ID*, const int* *piSensorChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: TSP

Sets the current position of the specified input signal channel (does not cause motion). For further details, see the description of the TSP command in the documentation of your controller.

Arguments:

ID ID of controller

piSensorChannelsArray array with input signal channels (e.g., sensor channels)

pdValueArray array with current positions in physical units

iArraySize the size of the arrays *piSensorChannelsArray* and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_VAR (int *ID*, const char * *szVariable*, const char* *szValue*)

Corresponding command: VAR

Sets a variable to a certain value.

Local variables can be set using PI_VAR() in macros only.

The variable is present in RAM only.

See "Variables" and "Controller Macros" in the controller User Manual for details.

Arguments:

ID ID of controller

szVariable name of the variable whose value is to be set

szValue is the value to which the variable is to be set. If omitted, the variable is deleted.

Returns:

TRUE if successful, **FALSE** otherwise.

BOOL PI_VCO (int *ID*, char* *szAxes*, BOOL* *pbValueArray*)

Corresponding command: VCO

Set velocity-control "on" or "off". When velocity-control is "on", the corresponding axes will move with the currently valid velocity. That velocity can be set with PI_VEL() (p. 112).

Arguments:

ID ID of controller

szAxes string with axes

pbValueArray modes for the specified axes, **TRUE** for "on", **FALSE** for "off"

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_VEL (int *ID*, const char* *szAxes*, const double* *pdValueArray*)

Corresponding command: VEL

Set the velocities to use during moves of *szAxes*. The PI_VEL() setting only takes effect when the given axis is in closed-loop operation (servo on).

Arguments:

ID ID of controller

szAxes string with axes

pdValueArray velocities for the axes

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_VLS (int *ID*, double *dSystemVelocity*)

Corresponding command: VLS

Sets the velocity for the moving platform of the Hexapod.

Arguments:

ID ID of controller

dSystemVelocity velocity value in physical units

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_VMA (int *ID*, const int* *piPiezoChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: VMA

Set upper PZT voltage soft limit of given piezo channel.

Arguments:

ID ID of controller

piPiezoChannelsArray array with piezo channels

pdValueArray upper limits for piezo voltage

iArraySize the size of the arrays *piPiezoChannelsArray* and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_VMI (int *ID*, const int* *piPiezoChannelsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: VMI

Set lower PZT voltage soft limit of given piezo channel.

Arguments:

ID ID of controller

piPiezoChannelsArray array with piezo channels

pdValueArray lower limits for piezo voltage

iArraySize the size of the arrays *piPiezoChannelsArray* and *pdValueArray*

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_WAC (int *ID*, const char * *szCondition*)

Corresponding command: WAC

Wait until a given condition of the following type occurs: a specified value is compared with a queried value according to a specified rule.

Can only be used in macros.

See also PI_MEX()

See "Controller Macros" in the controller User Manual for details.

Valid for:

E-861, C-867, C-887, C-863, C-884, E-871

Arguments:

ID ID of controller

szCondition string with condition to evaluate

Returns:

TRUE if successful, **FALSE** otherwise (see p. 10)

BOOL PI_WPA (int *ID*, const char* *szPassWord*, const char* *szAxes*, const int* *piParameterArray*)

Corresponding command: WPA

Gets values of the specified parameters from RAM and copies them to non-volatile memory. For each parameter you must specify a designator in *szAxes* and the parameter ID in the corresponding element of *piParameterArray*. See the user manual of the controller for a list of available parameters.

NOTICE: If current parameter values are incorrect, the system may malfunction. Be sure that you have the correct parameter settings before using PI_WPA().

Settings not saved with PI_WPA() will be lost when the controller is powered off or rebooted.

Arguments:

ID ID of controller

szPassWord The password for writing to non-volatile memory depends on the parameter. See the parameter overview and the description of the WPA command in the user manual of the controller.

szAxes string with designators. For each designator in szAxes one parameter value is copied.

piParameterArray Array with parameter IDs

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

7. Functions for GCS Commands for Wave Generator and DDL

The functions listed in this chapter are relevant for controllers which support the wave generator functionality and the Dynamic Digital Linearization (DDL).

The listed functions are based on the commands of the GCS. You can use a function only if the corresponding command is supported by your controller. See the user manual of the controller for the supported commands.

For all details regarding the functionality and arguments of commands, see the command descriptions in the user manual of the controller.

NOTE

If a query command is sent as string using `PI_Gcs_Commandset()` it is necessary to make sure that the size of the response string matches the size of the input buffer.

Otherwise it may happen that a response has not yet been retrieved completely before a next function is processed.

See "Functions for Sending and Reading Strings" (p. 20) for details.

Wave Generator

Each axis can be controlled by a "wave generator" which outputs user-specified patterns, so-called "waveforms". This feature is especially important in dynamic applications which require periodic, synchronous motion of the axes. The waveforms to be output are stored in "wave tables" in the controllers volatile memory—one waveform per wave table. Waveforms can be created based on predefined "curve" shapes. Programmable trigger inputs and outputs facilitate synchronization of external events. See "Wave Generator" in the user manual of the controller for more information and for examples.

During the wave generator output, data is recorded in "record tables" on the controller. See "Data Recording" in the controllers User Manual for more information.

The different software interfaces provided for the controller also support use of the wave generator. Waveforms can be defined, stored and displayed in and by the software in a more user-friendly way. If using the wave generator with PIMikroMove or LabView, read the descriptions in the associated software manual first.

Dynamic Digital Linearization (DDL)

The DDL option can be used in conjunction with the wave generator output in addition to the "normal" servo algorithm in closed-loop operation. The DDL makes it possible to achieve significantly better position accuracy for dynamic applications with periodic motion. DDL "observes" axis motion over one or more wave generator output cycles (DDL initialization). The information gathered is written to "DDL tables" and can then be used to refine the control output signals. The DDL feature must be expressly ordered. You can activate it after purchase and without opening the device. See "Dynamic Digital Linearization (DDL)" in the controllers User Manual for more information and for how to activate the DDL licence.

7.1. Functions Overview

Function	Short Description	Page
BOOL PI_DDL (int <i>ID</i> , int <i>iDdlTableId</i> , int <i>iOffsetOfFirstPointInDdlTable</i> , int <i>iNumberOfValues</i> , double* <i>pdValueArray</i>)	Transfer DDL data to a DDL data table on controller	117
BOOL PI_DPO (int <i>ID</i> , const char* <i>szAxes</i>)	Recalculate internal DDL processing parameters	118
BOOL PI_DTC (int <i>ID</i> , const int <i>piDdlTableIdsArray</i> , int <i>iArraySize</i>)	Clear given DDL table	118
BOOL PI_IsGeneratorRunning (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , BOOL* <i>pbValueArray</i> , int <i>iArraySize</i>)	Check if wave generators are running	118
BOOL PI_qDDL (int <i>ID</i> , const int* <i>piDdlTableIdsArrays</i> , int <i>iNumberOfDdlTables</i> , int <i>iOffset</i> , int <i>nrValues</i> , double** <i>pdValArray</i> , char* <i>szGcsArrayHeader</i> , int <i>iGcsArrayHeaderMaxSize</i>)	Read DDL tables asynchronously	118
BOOL PI_qDDL_SYNC (int <i>ID</i> , int <i>iDdlTableId</i> , int <i>iOffsetOfFirstPointInDdlTable</i> , int <i>iNumberOfValues</i> , double* <i>pdValueArray</i>)	Read DDL tables synchronously	119
BOOL PI_qDTL (int <i>ID</i> , const int* <i>piDdlTableIdsArray</i> , int* <i>piValueArray</i> , int <i>iArraySize</i>)	Get DDL table length	119
BOOL PI_qGWD (int <i>ID</i> , const int* <i>piWaveTableIdsArray</i> , int <i>iNumberOfWaveTables</i> , int <i>iOffset</i> , int <i>nrValues</i> , double** <i>pdValArray</i> , char* <i>szGcsArrayHeader</i> , int <i>iGcsArrayHeaderMaxSize</i>)	Read wave tables asynchronously	120
BOOL PI_qGWD_SYNC (int <i>ID</i> , int <i>iWaveTableId</i> , int <i>iOffsetOfFirstPointInWaveTable</i> , int <i>iNumberOfValues</i> , double* <i>pdValueArray</i>)	Read wave tables	120
BOOL PI_qTLT (int <i>ID</i> , int* <i>iNumberOfLinearizationTables</i>)	Get the number of DDL data tables	120
BOOL PI_qTWG (int <i>ID</i> , int* <i>iNumberOfWaveGenerators</i>)	Get the number of wave generators	121
BOOL PI_qTWS (int <i>ID</i> , const int* <i>piTriggerChannelIdsArrays</i> , int <i>iNumberOfTriggerChannels</i> , int <i>iOffset</i> , int <i>nrValues</i> , double** <i>pdValArray</i> , char* <i>szGcsArrayHeader</i> , int <i>iGcsArrayHeaderMaxSize</i>)	Read trigger line settings	121
BOOL PI_qWAV (int <i>ID</i> , const int* <i>piWaveTableIdsArray</i> , const int* <i>piParameterIdsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Get the parameters for a defined waveform	121
BOOL PI_qWGC (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , int* <i>piValueArray</i> , int <i>iArraySize</i>)	Get the number of wave generator output cycles	122
BOOL PI_qWGO (int <i>ID</i> , const int <i>piWaveGeneratorIdsArray</i> , int* <i>piValueArray</i> , int <i>iArraySize</i>)	Get the start/stop mode of the given wave generator	122
BOOL PI_qWMS (int <i>ID</i> , const int* <i>piWaveTableIdsArray</i> , int* <i>iMaximumWaveSizeArray</i> , int <i>iArraySize</i>)	Gets the maximum size of the wave storage	122
BOOL PI_qWOS (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Reads the current value of the offset which is added to the wave generator output	122
BOOL PI_qWSL (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , int* <i>piWaveTableIdsArray</i> , int <i>iArraySize</i>)	Get current setting of wave table selection	123
BOOL PI_qWTR (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , long* <i>piTableRateArray</i> , long* <i>piInterpolationTypeArray</i> , int <i>iArraySize</i>)	Gets the current wave generator table rate	123
BOOL PI_TWC (int <i>ID</i>)	Clears all output trigger settings for the wave generators	123

Function	Short Description	Page
BOOL PI_TWS (int <i>ID</i> , const int* <i>piTriggerChannelIdsArray</i> , const int* <i>piPointNumberArray</i> , const int* <i>piSwitchArray</i> , int <i>iArraySize</i>)	Sets trigger line actions to waveform points for the given trigger output line	123
BOOL PI_WAV_SINP (int <i>ID</i> , int <i>iWaveTableId</i> , int <i>iOffsetOfFirstPointInWaveTable</i> , int <i>iNumberOfPoints</i> , int <i>iAppendWave</i> , int <i>iCenterPointOfWave</i> , double <i>dAmplitudeOfWave</i> , double <i>dOffsetOfWave</i> , int <i>iSegmentLength</i>)	Define sine curve for given wave table	124
BOOL PI_WAV_LIN (int <i>ID</i> , int <i>iWaveTableId</i> , int <i>iOffsetOfFirstPointInWaveTable</i> , int <i>iNumberOfWavePoints</i> , int <i>iAppendWave</i> , int <i>iNumberOfSpeedUpDownPointsOfWave</i> , double <i>dAmplitudeOfWave</i> , double <i>dOffsetOfWave</i> , int <i>iSegmentLength</i>)	Define a single scan line curve for given wave table	125
BOOL PI_WAV_PNT (int <i>ID</i> , int <i>iWaveTableId</i> , int <i>iOffsetOfFirstPointInWaveTable</i> , int <i>iNumberOfWavePoints</i> , int <i>iAppendWave</i> , const double* <i>pdWavePoints</i>)	Create a user-defined curve for given wave table	126
BOOL PI_WAV_RAMP (int <i>ID</i> , int <i>iWaveTableId</i> , int <i>iOffsetOfFirstPointInWaveTable</i> , int <i>iNumberOfWavePoints</i> , int <i>iAppendWave</i> , int <i>iCenterPointOfWave</i> , int <i>iNumberOfSpeedUpDownPointsOfWave</i> , double <i>dAmplitudeOfWave</i> , double <i>dOffsetOfWave</i> , int <i>iSegmentLength</i>)	Define a ramp curve for given wave table	126
BOOL PI_WCL (int <i>ID</i> , int <i>iWaveTableIdsArray</i> , int <i>iArraySize</i>)	Clears the content of the given wave table	127
BOOL PI_WGC (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , const int* <i>piNumberOfCyclesArray</i> , int <i>iArraySize</i>)	Set the number of cycles for the wave generator output	128
BOOL PI_WGO (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , const int* <i>piStartModArray</i> , int <i>iArraySize</i>)	Start and stop the specified wave generator with the given mode	128
BOOL PI_WGR (int <i>ID</i>)	Restarts recording when the wave generator is running	128
BOOL PI_WOS (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , const double* <i>pdValueArray</i> , int <i>iArraySize</i>)	Sets an offset to the output of a wave generator	128
BOOL PI_WSL (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , const int* <i>piWaveTableIdsArray</i> , int <i>iArraySize</i>)	Wave table selection: connects a wave table to a wave generator	129
BOOL PI_WTR (int <i>ID</i> , const int* <i>piWaveGeneratorIdsArray</i> , const long* <i>piTableRateArray</i> , const long* <i>piInterpolationTypeArray</i> , int <i>iArraySize</i>)	Set wave generator table rate and interpolation type	129

7.2. Function Documentation

BOOL **PI_DDL** (int *ID*, int *iDdlTableId*, int *iOffsetOfFirstPointInDdlTable*, int *iNumberOfValues*, double* *pdValueArray*)

Corresponding command: DDL

Transfer dynamic digital linearization feature data to a DDL data table on the controller.

Arguments:

ID ID of controller

iDdlTableId number of the DDL data table to use.

iOffsetOfFirstPointInDdlTable index of first value to be transferred, (the first value in the DDL table has index 1)

iNumberOfValues number of values to be transferred

pdValueArray Array with the values for the DDL table (can have been filled with PI_qDDL()).

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_DPO (int *ID*, const char* *szAxes*)

Corresponding command: DPO

Dynamic Digital Linearization (DDL) Parameter Optimization. Recalculates the internal DDL processing parameters (Time Delay Max, ID 0x14000006, Time Delay Min, ID 0x14000007) for specified axis.

Arguments:

ID ID of controller

szAxes string with axes, if "" or **NULL** all axes are affected.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_DTC (int *ID*, const int *piDdlTableIdsArray*, int *iArraySize*)

Corresponding command: DTC

Dynamic Digital Linearization (DDL) table clear: clears the given DDL table.

PI_DTC() also stops a running DDL initialization process.

Arguments:

ID ID of controller

iDdlTableIdsArray array with the IDs of the data tables which are to be cleared.

iArraySize the size of the array *iDdlTableIdsArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_IsGeneratorRunning (int *ID*, const int* *piWaveGeneratorIdsArray*,
BOOL* *pbValueArray*, int *iArraySize*)

Corresponding command: #9 (ASCII 9)

Check if wave generators are running. If **TRUE** for a wave generator, the corresponding element of the array will be set to **TRUE**, otherwise to **FALSE**. If no wave generators were specified, only one boolean value is set and it is placed in *pbValueArray[0]*: It is **TRUE** if at least one wave generator is **TRUE**, **FALSE** otherwise.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray string with wave generator IDs, if "" or **NULL** all wave generators are queried and a global result placed in *pbValueArray[0]*

pbValueArray array to receive status of the wave generators, **TRUE** for wave generator in progress, **FALSE** otherwise

iArraySize the size of the array *pbValueArray* and *piWaveGeneratorIdsArray* (if not **NULL**)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDDL (int *ID*, const int* *piDdlTableIdsArrays*, int *iNumberOfDdlTables*, int
iOffset, int *nrValues*, double** *pdValArray*, char* *szGcsArrayHeader*, int
iGcsArrayHeaderMaxSize)

Corresponding command: DDL?

Read DDL tables. This function reads the data asynchronously, it will return as soon as the data header has been read and start a background process which reads in the data itself. See PI_GetAsyncBuffer() and PI_GetAsyncBufferIndex(). Detailed information about the data read in can be found in the header sent by the controller. See the GCS Array manual for details.

Only tables with the same length can be read at the same time. Because DDL tables do not have a common length, use PI_qDDL to read the table length before reading the table data.

Arguments:

ID ID of controller
piDdlTableIdsArray IDs of DDL tables
iNumberOfDdlTables number of DDL tables to read
iOffset index of first value to be read (starts with index 1)
nrValues number of values to read
pdValarray pointer to internal array to store the data; data from all tables read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call **PI_GetAsyncBufferIndex()** to find out how many data points have already been transferred
szGcsArrayHeader buffer to store the GCS array header
iGcsArrayHeaderMaxSize size of the buffer to store the GCS array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qDDL_SYNC (int *ID*, int *iDdlTableId*, int *iOffsetOfFirstPointInDdlTable*, int *iNumberOfValues*, double* *pdValueArray*)

Corresponding command: DDL?

Get the dynamic digital linearization feature data from a DDL data table from the controller. For large *N* values, communication timeout must be set long enough, otherwise a communication error may occur.

Arguments:

ID ID of controller
iDdlTableId ID of the DDL data table.
iOffsetOfFirstPointInDdlTable index in the DDL table of first value to be read, the first value in the DDL table has index 1
iNumberOfValues number of values to be read
pdValueArray Array to receive the values. Caller is responsible for providing enough space for *iNumberOfValues* doubles

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qDTL (int *ID*, const int* *piDdlTableIdsArray*, int* *piValueArray*, int *iArraySize*)

Corresponding command: DTL?

Get Dynamic Digital Linearizations Table Length.
 The table length should be read before reading the table data by PI_qDDL.

Arguments:

ID ID of controller
piDdlTableIdsArray array of the DDL table IDs
piValueArray array to receive the DDL table size
iArraySize the size of the arrays *piDdlTableIdsArray* and *piValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_qGWD (int ID, const int* piWaveTableIdsArrays, int
iNumberOfWaveTables, int iOffset, int nrValues, double** pdValArray, char*
szGcsArrayHeader, int iGcsArrayHeaderMaxSize)

```

Corresponding command: GWD?

Read wave tables. This function reads the data asynchronously, it will return as soon as the data header has been read and start a background process which reads in the data itself. See `PI_GetAsyncBuffer()` and `PI_GetAsyncBufferIndex()`. Detailed information about the data read in can be found in the header sent by the controller. See the GCS Array manual for details.

Depending on the waveform definition with `PI_WAV()`, the wave tables may have different lengths. But due to the definition of the GCS array as the response format, it is not possible to read tables with different lengths at the same time. You can ask with `PI_qWAV()` for the current length of the wave tables.

Arguments:

ID ID of controller

piWaveTableIdsArray IDs of wave tables

iNumberOfWaveTables number of wave tables to read

iOffset index of first value to be read (starts with index 1)

nrValues number of values to read

pdValarray pointer to internal array to store the data; data from all tables read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call `PI_GetAsyncBufferIndex()` to find out how many data points have already been transferred

szGcsArrayHeader buffer to store the GCS array header

iGcsArrayHeaderMaxSize size of the buffer to store the GCS array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

```

BOOL PI_qGWD_SYNC (int ID, int iWaveTableId, int
iOffsetOfFirstPointInWaveTable, int iNumberOfValues, double* pdValueArray )

```

Corresponding command: GWD?

Read the waveform associated with *iWaveTableId*.

Arguments:

ID ID of controller

iWaveTableId identifier for wave table

iOffsetOfFirstPointInWaveTable index of first point to be read, starts with index 1

iNumberOfPoints number of points to read

pdValuesArray array to receive the waveform. (Caller must provide enough space to store *iNumberOfPoints* double values!)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

```

BOOL PI_qTLT (int ID, int* iNumberOfLinearizationTables )

```

Corresponding command: TLT?

Get the number of DDL data tables.

Arguments:

ID ID of controller

piNumberOfLinearizationTables pointer to receive the number of DDL data tables.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTWG (int *ID*, int* *iNumberOfWaveGenerators*)

Corresponding command: TWG?

Get the number of wave generators.

Arguments:

ID ID of controller

iNumberOfWaveGenerators pointer to store the number of wave generators.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qTWS (int *ID*, const int* *piTriggerChannelIdsArrays*, int *iNumberOfTriggerChannels*, int *iOffset*, int *nrValues*, double** *pdValArray*, char* *szGcsArrayHeader*, int *iGcsArrayHeaderMaxSize*)

Corresponding command: TWS?

Reading of the trigger line settings made with PI_TWS for the waveform points. This function reads the data asynchronously, it will return as soon as the data header has been read and start a background process which reads in the data itself. See PI_GetAsyncBuffer() and PI_GetAsyncBufferIndex(). Detailed information about the data read in can be found in the header sent by the controller. See the GCS Array manual for details.

To query the waveform shape, use PI_qGWD.

Arguments:

ID ID of controller

piTriggerChannelIdsArray IDs of the trigger line (digital output line)

iNumberOfTriggerChannels number of trigger lines to read

iOffset index of first value to be read (starts with index 1)

nrValues number of values to read

pdValarray pointer to internal array to store the data; data from all trigger lines read will be placed in the same array with the values interspersed; the DLL will allocate enough memory to store all data, call PI_GetAsyncBufferIndex() to find out how many data points have already been transferred

szGcsArrayHeader buffer to store the GCS array header

iGcsArrayHeaderMaxSize size of the buffer to store the GCS array header, must be given to prevent buffer overflow

Returns:

TRUE if successful, **FALSE** otherwise

BOOL PI_qWAV (int *ID*, const int* *piWaveTableIdsArray*, const int* *piParameterIdsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: WAV?

Get the parameters for a defined waveform. For each desired parameter you must specify a wave table in *piWaveTableIdsArray* and a parameter ID in the corresponding element of *piParameterIdsArray*. The following parameter ID is valid:

1: Number of waveform points for currently defined wave.

Arguments:

ID ID of controller

piWaveTableIdsArray array with wave table IDs for which the parameter(s) should be read

piParameterIdsArray array with IDs of requested parameters

pdValueArray array to be filled with the values for the parameters

iArraySize the size of the arrays *piWaveTablesArray*, *piParameterIdsArray*, and *pdValueArray*

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qWGC (int *ID*, const int* *piWaveGeneratorIdsArray*, int* *piValueArray*, int *iArraySize*)

Corresponding command: WGC?

Get the number of wave generator output cycles set by PI_WGC (p. 128).

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators, if **NULL** all wave generators are queried

piValueArray array with number of cycles for each wave generator in *piWaveGeneratorIdsArray*

iArraySize the size of the arrays *piWaveGeneratorIdsArray* (if not **NULL**) and *piValueArray*.

Returns:

TRUE if no error, **FALSE** otherwise

BOOL PI_qWGO (int *ID*, const int *piWaveGeneratorIdsArray*, int* *piValueArray*, int *iArraySize*)

Corresponding command: WGO?

Get the start/stop mode of the given wave generator.

Note: Ask with PI_IsGeneratorRunning() for the current activation state of the wave generator. The reply shows if a wave generator is running or not, but does not contain any information about the wave generator start mode (e.g. with trigger output). With PI_qWGO you can ask for the last commanded wave generator start option (set by PI_WGO (p. 128)).

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators for which the start mode values will be read out, if **NULL** all wave generators are queried

piValueArray array with modes for each wave generator in *piWaveGeneratorIdsArray*

iArraySize the size of the arrays *piWaveGeneratorIdsArray* (if not **NULL**) and *piValueArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qWMS (int *ID*, const int* *piWaveTableIdsArray*, int* *iMaximumWaveSizeArray*, int *iArraySize*)

Corresponding command: WMS?

Gets the maximum size of the wave storage for *piWaveTableIdsArray*

Arguments:

ID ID of controller

piWaveTableIdsArray array with wave tables, if **NULL** all wave tables are queried.

piMaximumWaveSizeArray array to be filled with the maximum size of the wave storage for the corresponding wave table (number of points).

iArraySize the size of the arrays *piWaveTableIdsArray* (if not **NULL**) and *piMaximumWaveSizeArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qWOS (int *ID*, const int* *piWaveGeneratorIdsArray*, double* *pdValueArray*, int *iArraySize*)

Corresponding command: WOS?

Reads the current value of the offset which is added to the wave generator output.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators, if **NULL** all wave generators are queried.

pdValueArray array to receive the offsets of the wave generators.

iArraySize the size of the arrays *piWaveGeneratorIdsArray* (if not **NULL**) and *pdValueArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qWSL (int *ID*, const int* *piWaveGeneratorIdsArray*, int* *piWaveTableIdsArray*, int *iArraySize*)

Corresponding command: WSL?

Get current setting of wave table selection

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators, if **NULL** all wave generators are queried.

piWaveTableIdsArray array to receive the wave table IDs

iArraySize the size of the arrays *piWaveGeneratorIdsArray* (if not **NULL**) and *piWaveTableIdsArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_qWTR (int *ID*, const int* *piWaveGeneratorIdsArray*, long* *piTableRateArray*, long* *piInterpolationTypeArray*, int *iArraySize*)

Corresponding command: WTR?

Gets the current wave generator table rate, i.e. the number of servo-loop cycles used for wave generator output. Gets also the interpolation type used with table rate values > 1.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators, if **NULL** all wave generators are queried.

piTableRateArray array to receive the wave table rate.

piInterpolationTypeArray array to receive the interpolation type.

iArraySize the size of the arrays *piWaveGeneratorIdsArray* (if not **NULL**) and *piTableRateArray* and *piInterpolationTypeArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TWC (int *ID*)

Corresponding command: TWC

Clears all output trigger settings for the wave generators (the settings made with PI_TWS).

Arguments:

ID ID of controller

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_TWS (int *ID*, const int* *piTriggerChannelIdsArray*, const int* *piPointNumberArray*, const int* *piSwitchArray*, int *iArraySize*)

Corresponding command: TWS

Sets trigger line actions to waveform points for the given trigger output line.

The power-on default state of all points is low. Afterwards, the signal state of the trigger output line can be switched to "low" for all points using PI_TWC(). It is recommended to use PI_TWC() before trigger actions are set with PI_TWS().

For the selected trigger output line the generator trigger mode must be activated by PI_CTO().

Arguments:

ID ID of controller

piTriggerChannelIdsArray array with the trigger output lines.

piPointNumberArray array with the wave points.

piSwitchArray with the signal states of the trigger output lines at the wave points, if zero the trigger is set low, otherwise the trigger is set high.

iArraySize the number of points in the arrays *piTriggerChannelIdsArray*, *piPointNumberArray* and *piSwitchArray*.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

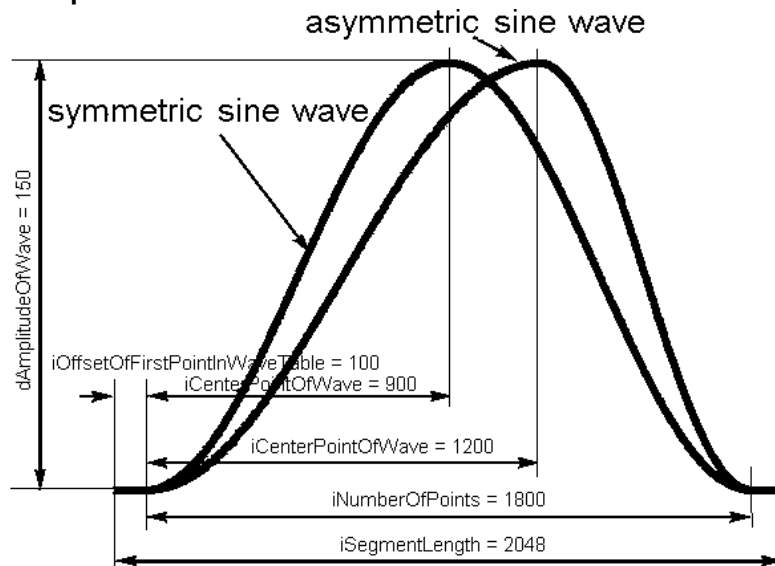
BOOL PI_WAV_SIN_P (int *ID*, int *iWaveTableId*, int *iOffsetOfFirstPointInWaveTable*, int *iNumberOfPoints*, int *iAppendWave*, int *iCenterPointOfWave*, double *dAmplitudeOfWave*, double *dOffsetOfWave*, int *iSegmentLength*)

Corresponding command: WAV

Define sine curve for given wave table.

To allow for flexible waveform shapes, a wave table can be divided into "segments". Each segment must be defined with a separate call of PI_WAV_SIN_P() or one of the other PI_WAV functions. In doing so, the *iAppendWave* argument (see below) is used to concatenate the segments so that they will form the final waveform. To change individual segments or to modify their order, the complete waveform must be recreated segment-by-segment. See the user manual of the controller for more information and for more examples.

Example:



Arguments:

ID ID of controller

iWaveTableId The wave table ID

iOffsetOfFirstPointInWaveTable The index of the starting point of the curve in the segment. Gives the phase shift. Lowest possible value is 0.

iNumberOfPoints The length of the curve as number of points.

iAppendWave Possible values (supported values depend on controller):

0 = clears the wave table and starts writing with the first point in the table

1 = adds the content of the defined segment to the already existing wave table contents (i.e. the values of the defined points are added to the existing values of that points)

2 = appends the defined segment to the already existing wave table content (i.e. concatenates segments to form one final waveform)

iCenterPointOfWave The index of the center point of the sine curve. Determines if the curve is symmetrically or not. Lowest possible value is 0.

dAmplitudeOfWave The amplitude of the sine curve.

dOffsetOfWave The offset of the sine curve.

iSegmentLength The length of the wave table segment as number of points. Only the number of points given by *iSegmentLength* will be written to the wave table. If the *iSegmentLength* value is

larger than the *iNumberOfPoints* value, the missing points in the segment are filled up with the endpoint value of the curve.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

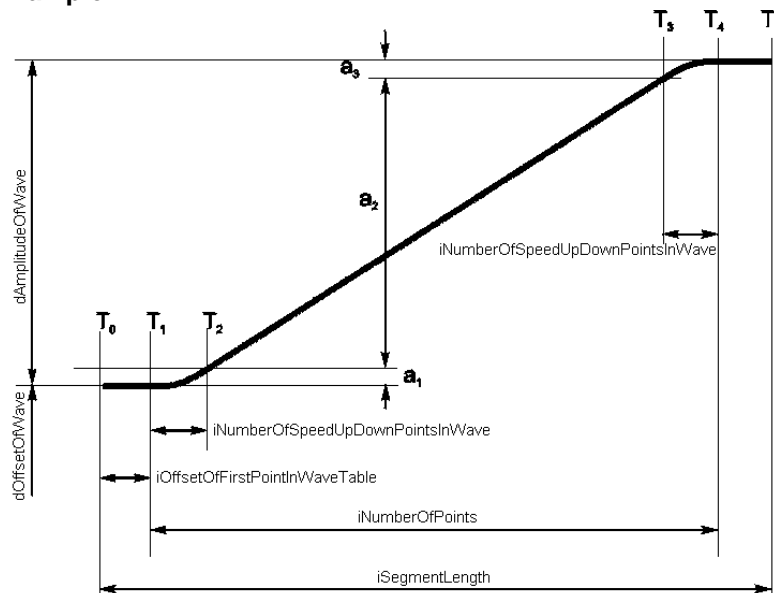
BOOL PI_WAV_LIN (int *ID*, int *iWaveTableId*, int *iOffsetOfFirstPointInWaveTable*, int *iNumberOfWavePoints*, int *iAppendWave*, int *iNumberOfSpeedUpDownPointsOfWave*, double *dAmplitudeOfWave*, double *dOffsetOfWave*, int *iSegmentLength*)

Corresponding command: WAV

Define a single scan line curve for given wave table.

To allow for flexible waveform shapes, a wave table can be divided into "segments". Each segment must be defined with a separate call of PI_WAV_LIN() or one of the other PI_WAV functions. In doing so, the *iAppendWave* argument (see below) is used to concatenate the segments so that they will form the final waveform. To change individual segments or to modify their order, the complete waveform must be recreated segment-by-segment. See the user manual of the controller for more information and for more examples.

Example:



Arguments:

ID ID of controller

iWaveTableId The ID of the wave table

iOffsetOfFirstPointInWaveTable The index of the starting point of the scan line in the segment.
Lowest possible value is 0.

iNumberOfWavePoints The length of the single scan line curve as number of points.

iAppendWave Possible values (supported values depend on controller):

0 = clears the wave table and starts writing with the first point in the table

1 = adds the content of the defined segment to the already existing wave table contents (i.e. the values of the defined points are added to the existing values of that points)

2 = appends the defined segment to the already existing wave table content (i.e. concatenates segments to form one final waveform)

dAmplitudeOfWave The amplitude of the scan line.

iNumberOfSpeedUpDownPointsOfWave The number of points for speed up and down.

dOffsetOfWave The offset of the scan line

iSegmentLength The length of the wave table segment as number of points. Only the number of points given by *iSegmentLength* will be written to the wave table. If the *iSegmentLength* value is larger than the *iNumberOfPoints* value, the missing points in the segment are filled up with the endpoint value of the curve.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_WAV_PNT (int *ID*, int *iWaveTableId*, int *iOffsetOfFirstPointInWaveTable*, int *iNumberOfWavePoints*, int *iAppendWave*, const double* *pdWavePoints*)

Corresponding command: WAV

Create a user-defined curve for given wave table.

To allow for flexible waveform shapes, a wave table can be divided into "segments". Each segment must be defined with a separate call of PI_WAV_PNT() or one of the other PI_WAV functions. In doing so, the *iAppendWave* argument (see below) is used to concatenate the segments so that they will form the final waveform. To change individual segments or to modify their order, the complete waveform must be recreated segment-by-segment. See the user manual of the controller for more information and for more examples.

Arguments:

ID ID of controller

iWaveTableId The ID of the wave table

iOffsetOfFirstPointInWaveTable The index of the starting point. Must be 1.

iNumberOfWavePoints The length of the user-defined curve as number of points.

iAppendWave Possible values (supported values depend on controller):

0 = clears the wave table and starts writing with the first point in the table

1 = adds the content of the defined segment to the already existing wave table contents (i.e. the values of the defined points are added to the existing values of that points)

2 = appends the defined segment to the already existing wave table content (i.e. concatenates segments to form one final waveform)

iSegmentLength The segment length, i.e. the number of points written to the wave table. Is identical to the *iNumberOfWavePoints* value.

pdWavePoints array with the wave points.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

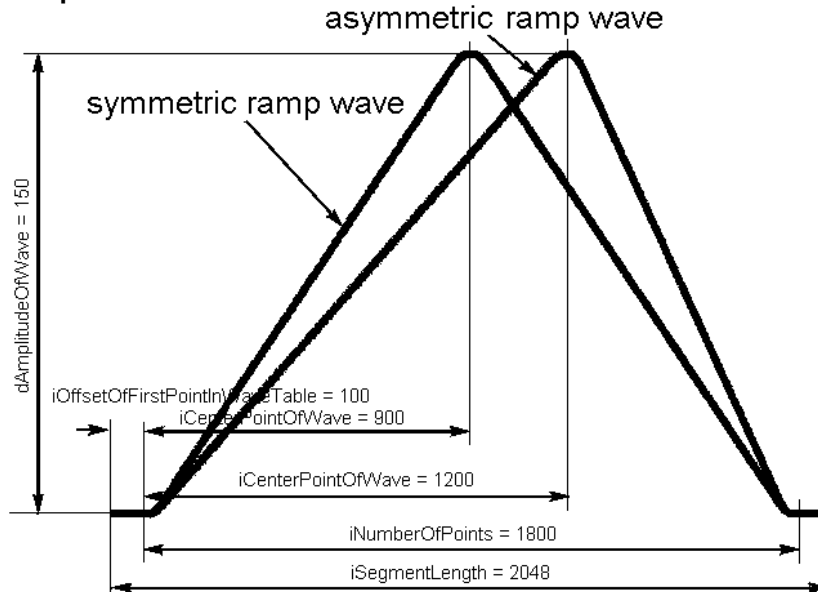
BOOL PI_WAV_RAMP (int *ID*, int *iWaveTableId*, int *iOffsetOfFirstPointInWaveTable*, int *iNumberOfWavePoints*, int *iAppendWave*, int *iCenterPointOfWave*, int *iNumberOfSpeedUpDownPointsOfWave*, double *dAmplitudeOfWave*, double *dOffsetOfWave*, int *iSegmentLength*)

Corresponding command: WAV

Define a ramp curve for given wave table.

To allow for flexible waveform shapes, a wave table can be divided into "segments". Each segment must be defined with a separate call of PI_WAV_RAMP() or one of the other PI_WAV functions. In doing so, the *iAppendWave* argument (see below) is used to concatenate the segments so that they will form the final waveform. To change individual segments or to modify their order, the complete waveform must be recreated segment-by-segment. See the user manual of the controller for more information and for more examples.

Example:



Arguments:

ID ID of controller

iWaveTableId The ID of the wave table

iOffsetOfFirstPointInWaveTable The index of the starting point of the ramp curve in the segment.
Gives the phase shift. Lowest possible value is 0.

iNumberOfWavePoints The length of the ramp curve as number of points.

iAppendWave Possible values (supported values depend on controller):

0 = clears the wave table and starts writing with the first point in the table

1 = adds the content of the defined segment to the already existing wave table contents (i.e. the values of the defined points are added to the existing values of that points)

2 = appends the defined segment to the already existing wave table content (i.e. concatenates segments to form one final waveform)

iCenterPointOfWave The index of the center point of the ramp curve. Determines if the curve is symmetrically or not. Lowest possible value is 0.

dAmplitudeOfWave The amplitude of the ramp curve.

iNumberOfSpeedUpDownPointsOfWave The number of points for speed up and down.

dOffsetOfWave The offset of the ramp curve.

iSegmentLength The length of the wave table segment as number of points. Only the number of points given by *iSegmentLength* will be written to the wave table. If the *iSegmentLength* value is larger than the *iNumberOfPoints* value, the missing points in the segment are filled up with the endpoint value of the curve.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_WCL (int *ID*, int *iWaveTableId*Array, int *iArraySize*)

Corresponding command: WCL

Clears the content of the given wave table.

As long as a wave generator is running, it is not possible to delete the connected wave table.

Arguments:

ID ID of controller

iWaveTableIdArray array with the IDs of the wave tables to be cleared.

iArraySize the size of the array *iWaveTableId*Array.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_WGC (int *ID*, const int* *piWaveGeneratorIdsArray*, const int* *piNumberOfCyclesArray*, int *iArraySize*)

Corresponding command: WGC

Set the number of cycles for the wave generator output (which is started with PI_WGO()).

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators

piNumberOfCyclesArray array with number of cycles for each wave generator in *piWaveGeneratorIdsArray*

iArraySize the size of the arrays *piWaveGeneratorIdsArray* and *piNumberOfCyclesArray*

Returns:

TRUE if successful, FALSE otherwise

BOOL PI_WGO (int *ID*, const int* *piWaveGeneratorIdsArray*, const int* *piStartModArray*, int *iArraySize*)

Corresponding command: WGO

Start and stop the specified wave generator with the given mode. Depending on the controller, starts also data recording.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators.

piStartModArray array with start modes for each wave generator in *piWaveGeneratorIdsArray* (hex format, optional decimal format)

iArraySize the size of the arrays *piWaveGeneratorIdsArray* and *piStartModArray*

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_WGR (int *ID*)

Corresponding command: WGR

Restarts recording when the wave generator is running (a first data recording cycle is started with PI_WGO() which starts the wave generator output).

The data recorder configuration can be made with PI_DRC() and PI_DRT. Data can be read with PI_qDRR() (p. 73).

Arguments:

ID ID of controller

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_WOS (int *ID*, const int* *piWaveGeneratorIdsArray*, const double* *pdValueArray*, int *iArraySize*)

Corresponding command: WOS

Sets an offset to the output of a wave generator. The current wave generator output is then created by adding the offset value to the current wave value:

Generator Output = Offset + Current Wave Value

Do not confuse the output-offset value set with PI_WOS() with the offset settings done during the waveform creation with the PI_WAV() functions. While the PI_WAV() offset belongs to only one waveform, the PI_WOS() offset is added to all waveforms which are output by the given wave generator.

Deleting wave table content with PI_WCL() has no effect on the offset settings for the wave generator output.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators.

pdValueArray array with the offsets of the wave generators.

iArraySize the size of the arrays *piWaveGeneratorIdsArray* and *pdValueArray*.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_WSL (int *ID*, const int* *piWaveGeneratorIdsArray*, const int* *piWaveTableIdsArray*, int *iArraySize*)

Corresponding command: WSL

Wave table selection: connects a wave table to a wave generator or disconnects the selected generator from any wave table.

Two or more generators can be connected to the same wave table, but a generator cannot be connected to more than one wave table.

Deleting wave table content with PI_WCL has no effect on the PI_WSL settings.

As long as a wave generator is running, it is not possible to change the connected wave table.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generators.

piWaveTableIdsArray array with the wave table ID. "0" disconnects the selected generator from any wave table.

iArraySize the size of the arrays *piWaveGeneratorIdsArray* and *piWaveTableIdsArray*.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

BOOL PI_WTR (int *ID*, const int* *piWaveGeneratorIdsArray*, const long* *piTableRateArray*, const long* *piInterpolationTypeArray*, int *iArraySize*)

Corresponding command: WTR

Set wave generator table rate and interpolation type:

Using PI_WTR(), you can "extend" the individual output cycles of the waveform. Depending on the controller, PI_WTR() furthermore determines the type of interpolation to use for the wave generator output. If the Wave Generator Table Rate is larger than 1, an interpolation helps to avoid sudden position jumps of the axis controlled by the wave generator.

Arguments:

ID ID of controller

piWaveGeneratorIdsArray array with wave generator IDs.

piTableRateArray array with the wave table rates.

piInterpolationTypeArray array with the interpolation types.

iArraySize the size of the arrays *piWaveGeneratorIdsArray* and *piTableRateArray* and *piInterpolationTypeArray*.

Returns:

TRUE if no error, FALSE otherwise (see p. 10)

8. Functions for Positioner Databases

The information in this chapter is relevant for controllers which support the use of positioner databases. Usually, positioner databases are located on the host PC. See the user manual of your controller to find out

- if the use of such positioner databases is supported for your controller
- the supported database format: PISTAGES3.DB (with the current controllers from PI) or PISTages2.dat and related databases (with older controllers from PI)

Positioner databases are located in the ...PI\GcsTranslator directory on the host PC. The location of the PI directory is that specified upon installation, usually in C:\ProgramData (Windows 7, 8, 10). If this directory does not exist, the program that needs the positioner databases will look in its own directory. In PIMikroMove, you can use the *Version Info* item in the controller menu or the *Search for controller software* item in the *Connections* menu to identify the GcsTranslator path.

See the user manual of your controller for how to install or update positioner databases on the host PC.

NOTES

Most of the controllers have a nonvolatile memory for parameter values. Therefore, after switching on, the correct parameter settings for the positioner connected may already be loaded.

- ➔ However, if you have loaded a parameter set from the positioner database and overwritten the original settings of the controller in the volatile memory, avoid saving the new settings in the nonvolatile memory of the controller. The original settings are active again after the controller has been switched off and on again or been rebooted.
-

8.1. PISTAGES3.DB and Related Databases

8.1.1. Available Databases

The PI GCS 2 DLL and the GCS-based host software from PI use the following databases:

- **PISTAGES3.DB**
Delivery includes parameter sets for all standard positioners from PI and PI miCos; is automatically saved to the PC when the PC software is installed. New parameter sets can be created, edited, and saved, e.g., using the PISTages3Editor or PIMikroMove PC software.
- **<Produkt>.db e.g.: M-xxxxxxx.db**
Includes the parameter set for a custom positioner. In order for the parameter set to be selected in the PC software, it must be added to the PISTAGES3.DB first, see "Installing Custom Positioner Databases" in the user manual of your controller.

8.1.2. Functions for PISTAGES3.DB

```

BOOL PI_WriteConfigurationFromDatabaseToController (int ID, const char* szFilter, const char*
szConfigurationName, char* szWarnings, int warningsBufferSize)
BOOL PI_WriteConfigurationFromDatabaseToControllerAndSave (int ID, const char* szFilter, const char*
szConfigurationName, char* szWarnings, int warningsBufferSize)
BOOL PI_ReadConfigurationFromControllerToDatabase (int ID, const char* szFilter, const char*
szConfigurationName, char* szWarnings, int warningsBufferSize)
BOOL PI_GetAvailableControllerConfigurationsFromDatabase (int ID, char* szConfigurationNames, int
configurationNamesBufferSize)
BOOL PI_GetAvailableControllerConfigurationsFromDatabaseByType (int ID, char*
szConfigurationNames, int configurationNamesBufferSize, unsigned int configurationType)

```

BOOL PI_WriteConfigurationFromDatabaseToController (int *ID*, const char* *szFilter*, const char* *szConfigurationName*, char* *szWarnings*, int *warningsBufferSize*)

Loads the specified configuration (parameter set) from the PISTages3.db positioner database and writes it to the volatile memory of the controller (exception: with C-891, the function writes to the nonvolatile memory).

The following actions are included:

- Configures the controller so that parameter setting is possible, e.g., sets the servo off
- Establishes the connection to the database
- Sets the parameters and checks for errors

Notes:

With PI_GetAvailableControllerConfigurationsFromDatabase(), the configurations existing in PISTages3.db for the connected controller can be listed.

It is strongly recommended to use PI_WriteConfigurationFromDatabaseToController() instead of PI_CST() (p. 38) which has the same functionality. PI_CST() is provided for compatibility reasons only.

Arguments:

ID ID of controller

szFilter string that assigns the configuration to an item of the controller. Consists of the key word (e.g., „axis“) and ID of the item (e.g., „4“). Filter examples: "axis1", "axis4"

szConfigurationName string with the name of a configuration existing in PISTages3.db (e.g., "V-551.4B")

szWarnings string that contains additional information if the configuration process was not error-free. Will be empty if return value is true.

warningsBufferSize buffer size of warning string.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_WriteConfigurationFromDatabaseToControllerAndSave (int *ID*, const char* *szFilter*, const char* *szConfigurationName*, char* *szWarnings*, int *warningsBufferSize*)

Loads the specified configuration (parameter set) from the PISTages3.db positioner database and writes it to the nonvolatile memory of the controller.

The following actions are included:

- Configures the controller so that parameter setting is possible, e.g., sets the servo off
- Establishes the connection to the database
- Sets the parameters and checks for errors

Notes:

With PI_GetAvailableControllerConfigurationsFromDatabase(), the configurations existing in PISTages3.db for the connected controller can be listed.

Arguments:

ID ID of controller

szFilter string that assigns the configuration to an item of the controller. Consists of the key word (e.g., „axis“) and ID of the item (e.g., „4“). Filter examples: "axis1", "axis4"

szConfigurationName string with the name of a configuration existing in PISTages3.db (e.g., "V-551.4B")

szWarnings string that contains additional information if the configuration process was not error-free. Will be empty if return value is true.

warningsBufferSize buffer size of warning string.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_ReadConfigurationFromControllerToDatabase (int *ID*, const char* *szFilter*, const char* *szConfigurationName*, char* *szWarnings*, int *warningsBufferSize*)

Reads the configuration from the controllers's volatile memory and writes it to the PIStages3.db positioner database.

Note:

It is strongly recommended to use `PI_ReadConfigurationFromControllerToDatabase()` instead of `PI_AddStage()` (p. 134) which has the same functionality. `PI_AddStage()` is provided for compatibility reasons only.

Arguments:

ID ID of controller

szFilter string that defines the configuration to be read from the controller. Consists of the key word (e.g., „axis“) and ID of the item (e.g., „4“). Filter examples: "axis1", "axis4"

szConfigurationName string that defines the name under which the configuration is to be saved in the PIStages3.db positioner database

szWarnings string that contains additional information if the reading/writing process was not error-free. Will be empty if return value is true.

warningsBufferSize buffer size of warning string.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_GetAvailableControllerConfigurationsFromDatabase (int *ID*, char* *szConfigurationNames*, int *configurationNamesBufferSize*)

Gets the available configurations for the connected controller from the PIStages3.db positioner database.

The configurations listed with `PI_GetAvailableControllerConfigurationsFromDatabase()` can be assigned to the items of the controller with `PI_WriteConfigurationFromDatabaseToController()`.

Note:

It is strongly recommended to use `PI_GetAvailableControllerConfigurationsFromDatabase()` instead of `PI_qVST()` (p. 102) which has the same functionality. `PI_qVST ()` is provided for compatibility reasons only.

Arguments:

ID ID of controller

szConfigurationNames string that contains the names of the configurations that are saved in the PIStages3.db positioner database for the connected controller

configurationNamesBufferSize buffer size of warning string.

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

BOOL PI_GetAvailableControllerConfigurationsFromDatabaseByType (int *ID*, char* *szConfigurationNames*, int *configurationNamesBufferSize*, unsigned int *configurationType*)

Gets the available configurations for the connected controller from the PIStages3.db positioner database.

The configurations listed with `PI_GetAvailableControllerConfigurationsFromDatabaseByType()` can be assigned to the items of the controller with `PI_WriteConfigurationFromDatabaseToController()`.

Similar to `PI_GetAvailableControllerConfigurationsFromDatabase()` but in addition, the returned configurations can be limited to certain types. Available types are:

`PI_CONFIGURATION_TYPE_ALL` - all configurations

`PI_CONFIGURATION_TYPE_USER` – all user configurations

`PI_CONFIGURATION_TYPE_STANDARD` – all standard configurations

`PI_CONFIGURATION_TYPE_CUSTOM` – all custom configurations

The different types can be combined, e.g.,

`"PI_CONFIGURATION_TYPE_USER | PI_CONFIGURATION_TYPE_STANDARD"`

will match all user and all standard configurations, but not any custom configuration.

Arguments:

ID ID of controller

szConfigurationNames string that contains the names of the configurations that are saved in the PIStages3.db positioner database for the connected controller

configurationNamesBufferSize buffer size of warning string.

configurationType type of configurations to be returned (see details above)

Returns:

TRUE if no error, **FALSE** otherwise (see p. 10)

8.2. PIStages2.dat and Related Databases

PIStages2.dat and related databases are supported by older PI controllers.

8.2.1. Available Databases

The PI GCS 2 DLL and the GCS-based host software from PI use the following databases for positioner parameters:

- **PIStages2.dat** and **PIMicosStages2.dat** contain parameter sets for all standard positioners from PI and PI miCos and are automatically installed on the host PC with the setup. They cannot be edited; should changes in a file become necessary, you must obtain a new version from PI or PI miCos and install it on your host PC.
- **PI_UserStages2.dat** allows you to create and save your own positioners. This database is created on the host PC the first time you connect positioners in the host software (i.e. the first time the PI_qVST() or PI_CST() functions of the PI GCS 2 library are used which is the case, for example, when VST? or CST are sent in PITerminal or the *Select connected stages* startup step is performed in PIMikroMove).
- **X-xxx.dat** files contain parameter sets for custom positioners delivered by PI or PI miCos. Those files are provided with the positioners and have to be copied to the host PC according to the accompanying instructions.
X-xxx.dat files cannot be edited; should changes become necessary, you must obtain a new version from PI or PI miCos.

8.2.2. Functions for the PI_UserStages2.dat Positioner Database

The PI GCS 2 DLL has functions allowing you to both define and save new positioners (parameter sets) to the PI_UserStages2.dat positioner database on the host PC (see “Function Description” below for more information). Being able to specify the parameters of a positioner and then save those parameters as a set under the positioner name makes it easier to connect to previously defined positioners.

You can create a new positioner parameter set by changing the positioner parameters with PI_SPA(). It is important to set the positioner parameters correctly. Note that the parameter which determines whether a positioner is “new” or not is the Stage Name parameter (ID 0x3C). If it is not specified, the PI_AddStage command will fail. See the user manual of the controller for a complete parameter list and parameter handling details.

You can ease the creation by loading an existing parameter set with PI_CST() and afterwards change the name and any other parameters, which differ, with PI_SPA(). PI_CST() “connects” a valid positioner, i.e. makes its parameter set active. It uses the corresponding parameters in the DAT files, so that you do not have to set them all by yourself.

To save the new positioner and thus make it available for a future connection with PI_CST(), use PI_AddStage() to add its parameter set to PI_UserStages2.dat. After adding it to PI_UserStages2.dat, the positioner will also appear in the list returned by PI_qVST().

If you want to remove a positioner from PI_UserStages2.dat call PI_RemoveStage().

It may be more comfortable to set the positioner parameters using the PIStageEditor (a GUI dialog). See the separate PI Stage Editor manual (SM144E) for a description of how to operate that graphic interface.

The PIStageEditor can also be started from PIMikroMove. This program provides several functions which ease creating and editing positioner parameter sets. For further information, refer to “Stage Editor” and “Tutorials - Frequently Asked Questions” in the PIMikroMove manual.

NOTES

The `PI_OpenUserStagesEditDialog()` or `PI_OpenPiStagesEditDialog()` functions are provided for compatibility reasons only and should not be used to open the PIStageEditor. Since the PIStageEditor is not modal, problems can occur when the calling application exits before the PIStageEditor window is closed. Please start the PIStageEditor either from PIMikroMove or via its executable.

BOOL PI_FUNC_DECL PI_AddStage (const int ID, char *const szAxes) BOOL PI_FUNC_DECL PI_RemoveStage (const int ID, char *szStageName)
--

8.2.3. Function Description

BOOL PI_AddStage (const int <i>ID</i> , const char* <i>szAxes</i>)
--

Adds the positioner specified for *szAxes* to the `PI_UserStages2.dat` file which contains user-defined positioners.

Arguments:

ID ID of controller
szAxes string with axis identifier.

Returns:

TRUE if successful, **FALSE**, if the buffer was too small to store the message

BOOL PI_RemoveStage (const int <i>ID</i> , char * <i>szStageName</i>)

Removes the positioner with the given name from the `PI_UserStages2.dat` file which contains user-defined positioners.

Arguments:

ID ID of controller
szStageName the positioner name as string.

Returns:

TRUE if successful, **FALSE**, if the buffer was too small to store the message

8.2.4. Troubleshooting

Problem:

Positioner database file cannot be opened, or positioner selection in host software is not possible. Error message arises saying that the positioner database does not have the correct revision.

Solution:

To support new hardware (controller or positioners), it is necessary to release new revisions of the positioner database files. Although PI aims for highest compatibility, the latest host software may not be able to work with older positioner database files. You can check the revision of your positioner database files using the *PIStageEditor* (see the PIStageEditor manual for details).

If your *PIStages2.dat* file does not have the correct revision, download the latest revision from www.pi.ws. For detailed update instructions see the user manual of the controller.

The *PI_UserStages2.dat* file is created the first time you connect positioners in the host software (i.e. the first time the *PI_qVST()* or *PI_CST()* functions of the PI GCS 2 DLL are used). If you have already a *PI_UserStages2.dat* file for your controller but this file cannot be opened with the latest software, proceed as follows:

- 1 Rename the existing *PI_UserStages2.dat* file on your host PC.
- 2 Create a new *PI_UserStages2.dat*. This can be done by calling the *PI_qVST()* or *PI_qCST()* functions of the PI GCS 2 DLL.
- 3 Open the new *PI_UserStages2.dat* in the *PIStageEditor*.
- 4 Import the content of the old (renamed) *PI_UserStages2.dat* file to the new file. See the *PIStageEditor* manual for details. Note that during the import procedure, the imported positioner parameter sets are converted to fit the new revision. Parameters which were not present in the old revision are set to default values which may need to be optimized.

8.3. Positioner Database Access with C-887.5xx Hexapod Controllers

A positioner type can be assigned to axes A and B of a C-887.5xx hexapod controller. With PI GCS DLL versions 3.17.0 and newer, the behavior of the *PI_qVST()* and *PI_CST()* functions is as follows:

PISTAGES3.DB exists on the PC	C-887.5xx provides parameter 0x3C*	PI_qVST() and PI_CST() for axes A and B ...
No	No	... run VST? and CST on the controller**
Yes	No	... run VST? and CST on the controller**
No	Yes	... run VST? and CST on the controller**
Yes	Yes	... run with PISTAGES3.DB

* Parameter 0x3C is available with the controller firmware version 2.5.2.1 and newer.

** VST? and CST access the *PIStages2.dat* database which is stored on the C-887.5xx controller. Note that in addition, CST switches the servo mode ON for axes A and B.

9. Error Codes

The error codes listed here are those of the *PI General Command Set*. As such, some are not relevant to your controller and will simply never occur with the systems this manual describes.

Controller errors

0	PI_CNTR_NO_ERROR	No error
1	PI_CNTR_PARAM_SYNTAX	Parameter syntax error
2	PI_CNTR_UNKNOWN_COMMAND	Unknown command
3	PI_CNTR_COMMAND_TOO_LONG	Command length out of limits or command buffer overrun
4	PI_CNTR_SCAN_ERROR	Error while scanning
5	PI_CNTR_MOVE_WITHOUT_REF_OR_NO_SERVO	Unallowable move attempted on unreferenced axis, or move attempted with servo off
6	PI_CNTR_INVALID_SGA_PARAM	Parameter for SGA not valid
7	PI_CNTR_POS_OUT_OF_LIMITS	Position out of limits
8	PI_CNTR_VEL_OUT_OF_LIMITS	Velocity out of limits
9	PI_CNTR_SET_PIVOT_NOT_POSSIBLE	Attempt to set pivot point while U,V and W not all 0
10	PI_CNTR_STOP	Controller was stopped by command
11	PI_CNTR_SST_OR_SCAN_RANGE	Parameter for SST or for one of the embedded scan algorithms out of range
12	PI_CNTR_INVALID_SCAN_AXES	Invalid axis combination for fast scan
13	PI_CNTR_INVALID_NAV_PARAM	Parameter for NAV out of range
14	PI_CNTR_INVALID_ANALOG_INPUT	Invalid analog channel
15	PI_CNTR_INVALID_AXIS_IDENTIFIER	Invalid axis identifier
16	PI_CNTR_INVALID_STAGE_NAME	Invalid positioner name
17	PI_CNTR_PARAM_OUT_OF_RANGE	Parameter out of range
18	PI_CNTR_INVALID_MACRO_NAME	Invalid macro name
19	PI_CNTR_MACRO_RECORD	Error while recording macro
20	PI_CNTR_MACRO_NOT_FOUND	Macro not found
21	PI_CNTR_AXIS_HAS_NO_BRAKE	Axis has no brake
22	PI_CNTR_DOUBLE_AXIS	Axis identifier specified more than once
23	PI_CNTR_ILLEGAL_AXIS	Illegal axis or channel
24	PI_CNTR_PARAM_NR	Incorrect number of parameters
25	PI_CNTR_INVALID_REAL_NR	Invalid floating point number
26	PI_CNTR_MISSING_PARAM	Parameter missing
27	PI_CNTR_SOFT_LIMIT_OUT_OF_RANGE	Soft limit out of range
28	PI_CNTR_NO_MANUAL_PAD	No manual pad found
29	PI_CNTR_NO_JUMP	No more step-response values
30	PI_CNTR_INVALID_JUMP	No step-response values recorded
31	PI_CNTR_AXIS_HAS_NO_REFERENCE	Axis has no reference sensor
32	PI_CNTR_STAGE_HAS_NO_LIM_SWITCH	Axis has no limit switch
33	PI_CNTR_NO_RELAY_CARD	No relay card installed
34	PI_CNTR_CMD_NOT_ALLOWED_FOR_STAGE	Command not allowed for selected positioner(s)

35	PI_CNTR_NO_DIGITAL_INPUT	No digital input installed
36	PI_CNTR_NO_DIGITAL_OUTPUT	No digital output configured
37	PI_CNTR_NO_MCM	No more MCM responses
38	PI_CNTR_INVALID_MCM	No MCM values recorded
39	PI_CNTR_INVALID_CNTR_NUMBER	Controller number invalid
40	PI_CNTR_NO_JOYSTICK_CONNECTED	No joystick configured
41	PI_CNTR_INVALID_EGE_AXIS	Invalid axis for electronic gearing, axis can not be slave
42	PI_CNTR_SLAVE_POSITION_OUT_OF_RANGE	Position of slave axis is out of range
43	PI_CNTR_COMMAND_EGE_SLAVE	Slave axis cannot be commanded directly when electronic gearing is enabled
44	PI_CNTR_JOYSTICK_CALIBRATION_FAILED	Calibration of joystick failed
45	PI_CNTR_REFERENCING_FAILED	Referencing failed
46	PI_CNTR_OPM_MISSING	OPM (Optical Power Meter) missing
47	PI_CNTR_OPM_NOT_INITIALIZED	OPM (Optical Power Meter) not initialized or cannot be initialized
48	PI_CNTR_OPM_COM_ERROR	OPM (Optical Power Meter) Communication Error
49	PI_CNTR_MOVE_TO_LIMIT_SWITCH_FAILED	Move to limit switch failed
50	PI_CNTR_REF_WITH_REF_DISABLED	Attempt to reference axis with referencing disabled
51	PI_CNTR_AXIS_UNDER_JOYSTICK_CONTROL	Selected axis is controlled by joystick
52	PI_CNTR_COMMUNICATION_ERROR	Controller detected communication error
53	PI_CNTR_DYNAMIC_MOVE_IN_PROCESS	Command is not allowed while the affected axis is in motion.
54	PI_CNTR_UNKNOWN_PARAMETER	Unknown parameter
55	PI_CNTR_NO_REP_RECORDED	No commands were recorded with REP
56	PI_CNTR_INVALID_PASSWORD	Password invalid
57	PI_CNTR_INVALID_RECORDER_CHAN	Data recorder table does not exist
58	PI_CNTR_INVALID_RECORDER_SRC_OPT	Source option does not exist; number too low or too high
59	PI_CNTR_INVALID_RECORDER_SRC_CHAN	Source ID (channel or axis) too low or too high
60	PI_CNTR_PARAM_PROTECTION	Protected Param: current Command Level (CCL) too low
61	PI_CNTR_AUTOZERO_RUNNING	Command execution not possible while Autozero is running
62	PI_CNTR_NO_LINEAR_AXIS	Autozero requires at least one linear axis
63	PI_CNTR_INIT_RUNNING	Initialization still in progress
64	PI_CNTR_READ_ONLY_PARAMETER	Parameter is read-only
65	PI_CNTR_PAM_NOT_FOUND	Parameter not found in non-volatile memory
66	PI_CNTR_VOL_OUT_OF_LIMITS	Voltage out of limits
67	PI_CNTR_WAVE_TOO_LARGE	Not enough memory available for requested wave curve
68	PI_CNTR_NOT_ENOUGH_DDL_MEMORY	Not enough memory available for DDL table; DDL can not be started
69	PI_CNTR_DDL_TIME_DELAY_TOO_LARGE	Time delay larger than DDL table; DDL can not be started
70	PI_CNTR_DIFFERENT_ARRAY_LENGTH	The requested arrays have different lengths; query them separately

71	PI_CNTR_GEN_SINGLE_MODE_RESTART	Attempt to restart the generator while it is running in single step mode
72	PI_CNTR_ANALOG_TARGET_ACTIVE	Motion commands and wave generator activation are not allowed when analog target is active
73	PI_CNTR_WAVE_GENERATOR_ACTIVE	Motion commands are not allowed when wave generator output is active; use WGO to disable generator output
74	PI_CNTR_AUTOZERO_DISABLED	No sensor channel or no piezo channel connected to selected axis (sensor and piezo matrix)
75	PI_CNTR_NO_WAVE_SELECTED	Generator started (WGO) without having selected a wave table (WSL).
76	PI_CNTR_IF_BUFFER_OVERRUN	Interface buffer did overrun and command couldn't be received correctly
77	PI_CNTR_NOT_ENOUGH_RECORDED_DATA	Data Record Table does not hold enough recorded data
78	PI_CNTR_TABLE_DEACTIVATED	Data Record Table is not configured for recording
79	PI_CNTR_OPENLOOP_VALUE_SET_WHEN_SERVO_ON	Open-loop commands (SVA, SVR) are not allowed when servo is on
80	PI_CNTR_RAM_ERROR	Hardware error affecting RAM
81	PI_CNTR_MACRO_UNKNOWN_COMMAND	Not macro command
82	PI_CNTR_MACRO_PC_ERROR	Macro counter out of range
83	PI_CNTR_JOYSTICK_ACTIVE	Joystick is active
84	PI_CNTR_MOTOR_IS_OFF	Motor is off
85	PI_CNTR_ONLY_IN_MACRO	Macro-only command
86	PI_CNTR_JOYSTICK_UNKNOWN_AXIS	Invalid joystick axis
87	PI_CNTR_JOYSTICK_UNKNOWN_ID	Joystick unknown
88	PI_CNTR_REF_MODE_IS_ON	Move without referenced positioner
89	PI_CNTR_NOT_ALLOWED_IN_CURRENT_MOTION_MODE	Command not allowed in current motion mode
90	PI_CNTR_DIO_AND_TRACING_NOT_POSSIBLE	No tracing possible while digital IOs are used on this HW revision. Reconnect to switch operation mode.
91	PI_CNTR_COLLISION	Move not possible, would cause collision
92	PI_CNTR_SLAVE_NOT_FAST_ENOUGH	Positioner is not capable of following the master. Check the gear ratio(SRA).
93	PI_CNTR_CMD_NOT_ALLOWED_WHILE_AXIS_IN_MOTION	This command is not allowed while the affected axis or its master is in motion.
94	PI_CNTR_OPEN_LOOP_JOYSTICK_ENABLED	Servo cannot be switched on when open-loop joystick control is enabled.
95	PI_CNTR_INVALID_SERVO_STATE_FOR_PARAMETER	This parameter cannot be changed in current servo mode.
96	PI_CNTR_UNKNOWN_STAGE_NAME	Unknown positioner name
97	PI_CNTR_INVALID_VALUE_LENGTH	Invalid length of value (too much characters)
98	PI_CNTR_AUTOZERO_FAILED	AutoZero procedure was not successful
99	PI_CNTR_SENSOR_VOLTAGE_OFF	Sensor voltage is off
100	PI_LABVIEW_ERROR	PI LabVIEW driver reports error. See source control for details.
200	PI_CNTR_NO_AXIS	No positioner connected to axis
201	PI_CNTR_NO_AXIS_PARAM_FILE	File with axis parameters not found
202	PI_CNTR_INVALID_AXIS_PARAM_FILE	Invalid axis parameter file

203	PI_CNTR_NO_AXIS_PARAM_BACKUP	Backup file with axis parameters not found
204	PI_CNTR_RESERVED_204	PI internal error code 204
205	PI_CNTR_SMO_WITH_SERVO_ON	SMO with servo on
206	PI_CNTR_UUDECODE_INCOMPLETE_HEADER	uudecode: incomplete header
207	PI_CNTR_UUDECODE_NOTHING_TO_DECODE	uudecode: nothing to decode
208	PI_CNTR_UUDECODE_ILLEGAL_FORMAT	uudecode: illegal UUE format
209	PI_CNTR_CRC32_ERROR	CRC32 error
210	PI_CNTR_ILLEGAL_FILENAME	Illegal file name (must be 8-0 format)
211	PI_CNTR_FILE_NOT_FOUND	File not found on controller
212	PI_CNTR_FILE_WRITE_ERROR	Error writing file on controller
213	PI_CNTR_DTR_HINDERS_VELOCITY_CHANGE	VEL command not allowed in DTR Command Mode
214	PI_CNTR_POSITION_UNKNOWN	Position calculations failed
215	PI_CNTR_CONN_POSSIBLY_BROKEN	The connection between controller and positioner may be broken
216	PI_CNTR_ON_LIMIT_SWITCH	The connected positioner has driven into a limit switch, some controllers need CLR to resume operation
217	PI_CNTR_UNEXPECTED_STRUT_STOP	Strut test command failed because of an unexpected strut stop
218	PI_CNTR_POSITION_BASED_ON_ESTIMATION	While MOV! is running position can only be estimated!
219	PI_CNTR_POSITION_BASED_ON_INTERPOLATION	Position was calculated during MOV motion
220	PI_CNTR_INTERPOLATION_FIFO_UNDERRUN	FIFO buffer underrun during interpolation
221	PI_CNTR_INTERPOLATION_FIFO_OVERFLOW	FIFO buffer overflow during interpolation
230	PI_CNTR_INVALID_HANDLE	Invalid handle
231	PI_CNTR_NO_BIOS_FOUND	No bios found
232	PI_CNTR_SAVE_SYS_CFG_FAILED	Save system configuration failed
233	PI_CNTR_LOAD_SYS_CFG_FAILED	Load system configuration failed
301	PI_CNTR_SEND_BUFFER_OVERFLOW	Send buffer overflow
302	PI_CNTR_VOLTAGE_OUT_OF_LIMITS	Voltage out of limits
303	PI_CNTR_OPEN_LOOP_MOTION_SET_WHEN_SERVO_ON	Open-loop motion attempted when servo ON
304	PI_CNTR_RECEIVING_BUFFER_OVERFLOW	Received command is too long
305	PI_CNTR_EEPROM_ERROR	Error while reading/writing EEPROM
306	PI_CNTR_I2C_ERROR	Error on I2C bus
307	PI_CNTR_RECEIVING_TIMEOUT	Timeout while receiving command
308	PI_CNTR_TIMEOUT	A lengthy operation has not finished in the expected time
309	PI_CNTR_MACRO_OUT_OF_SPACE	Insufficient space to store macro
310	PI_CNTR_EUI_OLDVERSION_CFGDATA	Configuration data has old version number
311	PI_CNTR_EUI_INVALID_CFGDATA	Invalid configuration data
333	PI_CNTR_HARDWARE_ERROR	Internal hardware error
400	PI_CNTR_WAV_INDEX_ERROR	Wave generator index error
401	PI_CNTR_WAV_NOT_DEFINED	Wave table not defined
402	PI_CNTR_WAV_TYPE_NOT_SUPPORTED	Wave type not supported
403	PI_CNTR_WAV_LENGTH_EXCEEDS_LIMIT	Wave length exceeds limit
404	PI_CNTR_WAV_PARAMETER_NR	Wave parameter number error
405	PI_CNTR_WAV_PARAMETER_OUT_OF_LIMIT	Wave parameter out of range

406	PI_CNTR_WGO_BIT_NOT_SUPPORTED	WGO command bit not supported
500	PI_CNTR_EMERGENCY_STOP_BUTTON_ACTIVATED	The \"red knob\" is still set and disables system
501	PI_CNTR_EMERGENCY_STOP_BUTTON_WAS_ACTIVATED	The \"red knob\" was activated and still disables system - reanimation required
502	PI_CNTR_REDUNDANCY_LIMIT_EXCEEDED	Position consistency check failed
503	PI_CNTR_COLLISION_SWITCH_ACTIVATED	Hardware collision sensor(s) are activated
504	PI_CNTR_FOLLOWING_ERROR	Strut following error occurred, e.g. caused by overload or encoder failure
505	PI_CNTR_SENSOR_SIGNAL_INVALID	One sensor signal is not valid
506	PI_CNTR_SERVO_LOOP_UNSTABLE	Servo loop was unstable due to wrong parameter setting and switched off to avoid damage.
507	PI_CNTR_LOST_SPI_SLAVE_CONNECTION	digital connection to external spi slave device is lost
508	PI_CNTR_MOVE_ATTEMPT_NOT_PERMITTED	Move attempt not permitted due to customer or limit settings
509	PI_CNTR_TRIGGER_EMERGENCY_STOP	Emergency stop caused by trigger input
530	PI_CNTR_CS_DOES_NOT_EXIST	A command refers to a coordinate system that does not exist
531	PI_CNTR_PARENT_CS_DOES_NOT_EXIST	A command refers to a coordinate system that has no parent node
532	PI_CNTR_CS_IN_USE	Attempt to delete or change a coordinate system that is in use
533	PI_CNTR_CS_DEFINITION_IS_CYCLIC	Definition of a coordinate system is cyclic
536	PI_CNTR_HEXAPOD_IN_MOTION	Coordinate system cannot be defined as long as Hexapod is in motion
537	PI_CNTR_CS_TYPE_CANNOT_BE_ENABLED	Coordinate system type is not intended for manual enabling
539	PI_CNTR_CS_PARENT_IDENTICAL_TO_CHILD	A coordinate system cannot be linked to itself
540	PI_CNTR_CS_DEFINITION_INCONSISTENT	Coordinate system definition is erroneous or not complete (replace or delete it)
542	PI_CNTR_CS_NOT_IN_SAME_CHAIN	The coordinate systems are not part of the same chain
543	PI_CNTR_CS_MEMORY_FULL	Unused coordinate system must be deleted before new coordinate system can be stored
544	PI_CNTR_SPI_COMMAND_NOT_SUPPORTED	With this coordinate system type SPI usage is not supported
545	PI_CNTR_SOFTLIMITS_INVALID	Soft limits invalid due to changes in coordinate system
546	PI_CNTR_CS_WRITE_PROTECTED	Coordinate system is write protected
547	PI_CNTR_CS_CONTENT_FROM_CONFIG_FILE	Coordinate system cannot be changed because its content is loaded from a configuration file
548	PI_CNTR_CS_CANNOT_BE_LINKED	Coordinate system may not be linked
549	PI_CNTR_KSB_CS_ROTATION_ONLY	A KSB-type coordinate system can only be rotated by multiples of 90 degrees
551	PI_CNTR_CS_DATA_CANNOT_BE_QUERIED	This query is not supported for this coordinate system type
552	PI_CNTR_CS_COMBINATION_DOES_NOT_EXIST	This combination of work and tool coordinate systems does not exist
553	PI_CNTR_CS_COMBINATION_INVALID	The combination must consist of one work and one tool coordinate system
554	PI_CNTR_CS_TYPE_DOES_NOT_EXIST	This coordinate system type does not exist

555	PI_CNTR_UNKNOWN_ERROR	BasMac: unknown controller error
556	PI_CNTR_CS_TYPE_NOT_ENABLED	No coordinate system of this type is enabled
557	PI_CNTR_CS_NAME_INVALID	Name of coordinate system is invalid
558	PI_CNTR_CS_GENERAL_FILE_MISSING	File with stored CS systems is missing or erroneous
559	PI_CNTR_CS_LEVELING_FILE_MISSING	File with leveling CS is missing or erroneous
601	PI_CNTR_NOT_ENOUGH_MEMORY	Not enough memory
602	PI_CNTR_HW_VOLTAGE_ERROR	Hardware voltage error
603	PI_CNTR_HW_TEMPERATURE_ERROR	Hardware temperature out of range
604	PI_CNTR_POSITION_ERROR_TOO_HIGH	Position error of any axis in the system is too high
606	PI_CNTR_INPUT_OUT_OF_RANGE	Maximum value of input signal has been exceeded
607	PI_CNTR_NO_INTEGER	Value is not integer
608	PI_CNTR_FAST_ALIGNMENT_PROCESS_IS_NOT_RUNNING	Fast alignment process cannot be paused because it is not running
609	PI_CNTR_FAST_ALIGNMENT_PROCESS_IS_NOT_PAUSED	Fast alignment process cannot be restarted/resumed because it is not paused
650	PI_CNTR_UNABLE_TO_SET_PARAM_WITH_SPA	Parameter could not be set with SPA - SEP needed?
651	PI_CNTR_PHASE_FINDING_ERROR	Phase finding error
652	PI_CNTR_SENSOR_SETUP_ERROR	Sensor setup error
653	PI_CNTR_SENSOR_COMM_ERROR	Sensor communication error
654	PI_CNTR_MOTOR_AMPLIFIER_ERROR	Motor amplifier error
655	PI_CNTR_OVER_CURR_PROTEC_TRIGGERED_BY_I2T	Overcurrent protection triggered by I2T-module
656	PI_CNTR_OVER_CURR_PROTEC_TRIGGERED_BY_AMP_MODULE	Overcurrent protection triggered by amplifier module
657	PI_CNTR_SAFETY_STOP_TRIGGERED	Safety stop triggered
658	PI_SENSOR_OFF	Sensor off?
700	PI_CNTR_COMMAND_NOT_ALLOWED_IN_EXTERNAL_MODE	Command not allowed in external mode
710	PI_CNTR_EXTERNAL_MODE_ERROR	External mode communication error
715	PI_CNTR_INVALID_MODE_OF_OPERATION	Invalid mode of operation
716	PI_CNTR_FIRMWARE_STOPPED_BY_CMD	Firmware stopped by command (#27)
717	PI_CNTR_EXTERNAL_MODE_DRIVER_MISSING	External mode driver missing
718	PI_CNTR_CONFIGURATION_FAILURE_EXTERNAL_MODE	Missing or incorrect configuration of external mode
719	PI_CNTR_EXTERNAL_MODE_CYCLETIME_INVALID	External mode cycletime invalid
720	PI_CNTR_BRAKE_ACTIVATED	Brake is activated
725	PI_CNTR_DRIVE_STATE_TRANSITION_ERROR	Drive state transition error
731	PI_CNTR_SURFACEDETECTION_RUNNING	Command not allowed while surface detection is running
732	PI_CNTR_SURFACEDETECTION_FAILED	Last surface detection failed
733	PI_CNTR_FIELDBUS_IS_ACTIVE	Fieldbus is active and is blocking GCS control commands
1000	PI_CNTR_TOO_MANY_NESTED_MACROS	Too many nested macros
1001	PI_CNTR_MACRO_ALREADY_DEFINED	Macro already defined
1002	PI_CNTR_NO_MACRO_RECORDING	Macro recording not activated
1003	PI_CNTR_INVALID_MAC_PARAM	Invalid parameter for MAC
1004	PI_CNTR_MACRO_DELETE_ERROR	Deleting macro failed

1005	PI_CNTR_CONTROLLER_BUSY	Controller is busy with some lengthy operation (e.g. reference move, fast scan algorithm)
1006	PI_CNTR_INVALID_IDENTIFIER	Invalid identifier (invalid special characters, ...)
1007	PI_CNTR_UNKNOWN_VARIABLE_OR_ARGUMENT	Variable or argument not defined
1008	PI_CNTR_RUNNING_MACRO	Controller is (already) running a macro
1009	PI_CNTR_MACRO_INVALID_OPERATOR	Invalid or missing operator for condition. Check necessary spaces around operator.
1010	PI_CNTR_MACRO_NO_ANSWER	No answer was received while executing WAC/MEX/JRC/...
1011	PI_CMD_NOT_VALID_IN_MACRO_MODE	Command not valid during macro execution
1012	PI_CNTR_ERROR_IN_MACRO	Error occurred during macro execution
1024	PI_CNTR_MOTION_ERROR	Motion error: position error too large, servo is switched off automatically
1025	PI_CNTR_MAX_MOTOR_OUTPUT_REACHED	Maximum motor output reached
1063	PI_CNTR_EXT_PROFILE_UNALLOWED_CMD	User Profile Mode: Command is not allowed, check for required preparatory commands
1064	PI_CNTR_EXT_PROFILE_EXPECTING_MOTION_ERROR	User Profile Mode: First target position in User Profile is too far from current position
1065	PI_CNTR_PROFILE_ACTIVE	Controller is (already) in User Profile Mode
1066	PI_CNTR_PROFILE_INDEX_OUT_OF_RANGE	User Profile Mode: Block or Data Set index out of allowed range
1071	PI_CNTR_PROFILE_OUT_OF_MEMORY	User Profile Mode: Out of memory
1072	PI_CNTR_PROFILE_WRONG_CLUSTER	User Profile Mode: Cluster is not assigned to this axis
1073	PI_CNTR_PROFILE_UNKNOWN_CLUSTER_IDENTIFIER	Unknown cluster identifier
1090	PI_CNTR_TOO_MANY_TCP_CONNECTIONS_OPEN	There are too many open tcpip connections
2000	PI_CNTR_ALREADY_HAS_SERIAL_NUMBER	Controller already has a serial number
4000	PI_CNTR_SECTOR_ERASE_FAILED	Sector erase failed
4001	PI_CNTR_FLASH_PROGRAM_FAILED	Flash program failed
4002	PI_CNTR_FLASH_READ_FAILED	Flash read failed
4003	PI_CNTR_HW_MATCHCODE_ERROR	HW match code missing/invalid
4004	PI_CNTR_FW_MATCHCODE_ERROR	FW match code missing/invalid
4005	PI_CNTR_HW_VERSION_ERROR	HW version missing/invalid
4006	PI_CNTR_FW_VERSION_ERROR	FW version missing/invalid
4007	PI_CNTR_FW_UPDATE_ERROR	FW update failed
4008	PI_CNTR_FW_CRC_PAR_ERROR	FW Parameter CRC wrong
4009	PI_CNTR_FW_CRC_FW_ERROR	FW CRC wrong
5000	PI_CNTR_INVALID_PCC_SCAN_DATA	PicoCompensation scan data is not valid
5001	PI_CNTR_PCC_SCAN_RUNNING	PicoCompensation is running, some actions can not be executed during scanning/recording
5002	PI_CNTR_INVALID_PCC_AXIS	Given axis can not be defined as PPC axis
5003	PI_CNTR_PCC_SCAN_OUT_OF_RANGE	Defined scan area is larger than the travel range
5004	PI_CNTR_PCC_TYPE_NOT_EXISTING	Given PicoCompensation type is not defined
5005	PI_CNTR_PCC_PAM_ERROR	PicoCompensation parameter error
5006	PI_CNTR_PCC_TABLE_ARRAY_TOO_LARGE	PicoCompensation table is larger than maximum table length
5100	PI_CNTR_NEXLINE_ERROR	Common error in Nexline firmware module
5101	PI_CNTR_CHANNEL_ALREADY_USED	Output channel for Nexline can not be redefined for other usage

5102	PI_CNTR_NEXLINE_TABLE_TOO_SMALL	Memory for Nexline signals is too small
5103	PI_CNTR_RNP_WITH_SERVO_ON	RNP can not be executed if axis is in closed loop
5104	PI_CNTR_RNP_NEEDED	relax procedure (RNP) needed
5200	PI_CNTR_AXIS_NOT_CONFIGURED	Axis must be configured for this action
5300	PI_CNTR_FREQU_ANALYSIS_FAILED	Frequency analysis failed
5301	PI_CNTR_FREQU_ANALYSIS_RUNNING	Another frequency analysis is running
6000	PI_CNTR_SENSOR_ABS_INVALID_VALUE	Invalid preset value of absolute sensor
6001	PI_CNTR_SENSOR_ABS_WRITE_ERROR	Error while writing to sensor
6002	PI_CNTR_SENSOR_ABS_READ_ERROR	Error while reading from sensor
6003	PI_CNTR_SENSOR_ABS_CRC_ERROR	Checksum error of absolute sensor
6004	PI_CNTR_SENSOR_ABS_ERROR	General error of absolute sensor
6005	PI_CNTR_SENSOR_ABS_OVERFLOW	Overflow of absolute sensor position

Interface errors

0	COM_NO_ERROR	No error occurred during function call
-1	COM_ERROR	Error during com operation (could not be specified)
-2	SEND_ERROR	Error while sending data
-3	REC_ERROR	Error while receiving data
-4	NOT_CONNECTED_ERROR	Not connected (no port with given ID open)
-5	COM_BUFFER_OVERFLOW	Buffer overflow
-6	CONNECTION_FAILED	Error while opening port
-7	COM_TIMEOUT	Timeout error
-8	COM_MULTILINE_RESPONSE	There are more lines waiting in buffer
-9	COM_INVALID_ID	There is no interface or DLL handle with the given ID
-10	COM_NOTIFY_EVENT_ERROR	Event/message for notification could not be opened
-11	COM_NOT_IMPLEMENTED	Function not supported by this interface type
-12	COM_ECHO_ERROR	Error while sending "echoed" data
-13	COM_GPIB_EDVR	IEEE488: System error
-14	COM_GPIB_ECIC	IEEE488: Function requires GPIB board to be CIC
-15	COM_GPIB_ENOL	IEEE488: Write function detected no listeners
-16	COM_GPIB_EADR	IEEE488: Interface board not addressed correctly
-17	COM_GPIB_EARG	IEEE488: Invalid argument to function call
-18	COM_GPIB_ESAC	IEEE488: Function requires GPIB board to be SAC
-19	COM_GPIB_EABO	IEEE488: I/O operation aborted
-20	COM_GPIB_ENEB	IEEE488: Interface board not found
-21	COM_GPIB_EDMA	IEEE488: Error performing DMA
-22	COM_GPIB_EOIP	IEEE488: I/O operation started before previous operation completed
-23	COM_GPIB_ECAP	IEEE488: No capability for intended operation
-24	COM_GPIB_EFSO	IEEE488: File system operation error
-25	COM_GPIB_EBUS	IEEE488: Command error during device call
-26	COM_GPIB_ESTB	IEEE488: Serial poll-status byte lost
-27	COM_GPIB_ESRQ	IEEE488: SRQ remains asserted
-28	COM_GPIB_ETAB	IEEE488: Return buffer full
-29	COM_GPIB_ELCK	IEEE488: Address or board locked

-30	COM_RS_INVALID_DATA_BITS	RS-232: 5 data bits with 2 stop bits is an invalid combination, as is 6, 7, or 8 data bits with 1.5 stop bits
-31	COM_ERROR_RS_SETTINGS	RS-232: Error configuring the COM port
-32	COM_INTERNAL_RESOURCES_ERROR	Error dealing with internal system resources (events, threads, ...)
-33	COM_DLL_FUNC_ERROR	A DLL or one of the required functions could not be loaded
-34	COM_FTDIUSB_INVALID_HANDLE	FTDIUSB: invalid handle
-35	COM_FTDIUSB_DEVICE_NOT_FOUND	FTDIUSB: device not found
-36	COM_FTDIUSB_DEVICE_NOT_OPENED	FTDIUSB: device not opened
-37	COM_FTDIUSB_IO_ERROR	FTDIUSB: IO error
-38	COM_FTDIUSB_INSUFFICIENT_RESOURCES	FTDIUSB: insufficient resources
-39	COM_FTDIUSB_INVALID_PARAMETER	FTDIUSB: invalid parameter
-40	COM_FTDIUSB_INVALID_BAUD_RATE	FTDIUSB: invalid baud rate
-41	COM_FTDIUSB_DEVICE_NOT_OPENED_FOR_ERASE	FTDIUSB: device not opened for erase
-42	COM_FTDIUSB_DEVICE_NOT_OPENED_FOR_WRITE	FTDIUSB: device not opened for write
-43	COM_FTDIUSB_FAILED_TO_WRITE_DEVICE	FTDIUSB: failed to write device
-44	COM_FTDIUSB_EEPROM_READ_FAILED	FTDIUSB: EEPROM read failed
-45	COM_FTDIUSB_EEPROM_WRITE_FAILED	FTDIUSB: EEPROM write failed
-46	COM_FTDIUSB_EEPROM_ERASE_FAILED	FTDIUSB: EEPROM erase failed
-47	COM_FTDIUSB_EEPROM_NOT_PRESENT	FTDIUSB: EEPROM not present
-48	COM_FTDIUSB_EEPROM_NOT_PROGRAMMED	FTDIUSB: EEPROM not programmed
-49	COM_FTDIUSB_INVALID_ARGS	FTDIUSB: invalid arguments
-50	COM_FTDIUSB_NOT_SUPPORTED	FTDIUSB: not supported
-51	COM_FTDIUSB_OTHER_ERROR	FTDIUSB: other error
-52	COM_PORT_ALREADY_OPEN	Error while opening the COM port: was already open
-53	COM_PORT_CHECKSUM_ERROR	Checksum error in received data from COM port
-54	COM_SOCKET_NOT_READY	Socket not ready, you should call the function again
-55	COM_SOCKET_PORT_IN_USE	Port is used by another socket
-56	COM_SOCKET_NOT_CONNECTED	Socket not connected (or not valid)
-57	COM_SOCKET_TERMINATED	Connection terminated (by peer)
-58	COM_SOCKET_NO_RESPONSE	Can't connect to peer
-59	COM_SOCKET_INTERRUPTED	Operation was interrupted by a nonblocked signal
-60	COM_PCI_INVALID_ID	No device with this ID is present
-61	COM_PCI_ACCESS_DENIED	Driver could not be opened (on Vista: run as administrator!)
-62	COM_SOCKET_HOST_NOT_FOUND	Host not found
-63	COM_DEVICE_CONNECTED	Device already connected

DLL errors

-1001	PI_UNKNOWN_AXIS_IDENTIFIER	Unknown axis identifier
-1002	PI_NR_NAV_OUT_OF_RANGE	Number for NAV out of range--must be in [1.10000]
-1003	PI_INVALID_SGA	Invalid value for SGA--must be one of 1, 10, 100, 1000
-1004	PI_UNEXPECTED_RESPONSE	Controller sent unexpected response
-1005	PI_NO_MANUAL_PAD	No manual control pad installed, calls to SMA and related commands are not

		allowed
-1006	PI_INVALID_MANUAL_PAD_KNOB	Invalid number for manual control pad knob
-1007	PI_INVALID_MANUAL_PAD_AXIS	Axis not currently controlled by a manual control pad
-1008	PI_CONTROLLER_BUSY	Controller is busy with some lengthy operation (e.g., reference move, fast scan algorithm)
-1009	PI_THREAD_ERROR	Internal error--could not start thread
-1010	PI_IN_MACRO_MODE	Controller is (already) in macro mode--command not valid in macro mode
-1011	PI_NOT_IN_MACRO_MODE	Controller not in macro mode--command not valid unless macro mode active
-1012	PI_MACRO_FILE_ERROR	Could not open file to write or read macro
-1013	PI_NO_MACRO_OR_EMPTY	No macro with given name on controller, or macro is empty
-1014	PI_MACRO_EDITOR_ERROR	Internal error in macro editor
-1015	PI_INVALID_ARGUMENT	One or more arguments given to function is invalid (empty string, index out of range, ...)
-1016	PI_AXIS_ALREADY_EXISTS	Axis identifier is already in use by a connected positioner
-1017	PI_INVALID_AXIS_IDENTIFIER	Invalid axis identifier
-1018	PI_COM_ARRAY_ERROR	Could not access array data in COM server
-1019	PI_COM_ARRAY_RANGE_ERROR	Range of array does not fit the number of parameters
-1020	PI_INVALID_SPA_CMD_ID	Invalid parameter ID given to SPA or SPA?
-1021	PI_NR_AVG_OUT_OF_RANGE	Number for AVG out of range--must be >0
-1022	PI_WAV_SAMPLES_OUT_OF_RANGE	Incorrect number of samples given to WAV
-1023	PI_WAV_FAILED	Generation of wave failed
-1024	PI_MOTION_ERROR	Motion error: position error too large, servo is switched off automatically
-1025	PI_RUNNING_MACRO	Controller is (already) running a macro
-1026	PI_PZT_CONFIG_FAILED	Configuration of PZT positioner or amplifier failed
-1027	PI_PZT_CONFIG_INVALID_PARAMS	Current settings are not valid for desired configuration
-1028	PI_UNKNOWN_CHANNEL_IDENTIFIER	Unknown channel identifier
-1029	PI_WAVE_PARAM_FILE_ERROR	Error while reading/writing wave generator parameter file
-1030	PI_UNKNOWN_WAVE_SET	Could not find description of wave form. Maybe WG.INI is missing?
-1031	PI_WAVE_EDITOR_FUNC_NOT_LOADED	The WGWaveEditor DLL function was not found at startup
-1032	PI_USER_CANCELLED	The user cancelled a dialog
-1033	PI_C844_ERROR	Error from C-844 Controller
-1034	PI_DLL_NOT_LOADED	DLL necessary to call function not loaded, or function not found in DLL
-1035	PI_PARAMETER_FILE_PROTECTED	The open parameter file is protected and cannot be edited
-1036	PI_NO_PARAMETER_FILE_OPENED	There is no parameter file open
-1037	PI_STAGE_DOES_NOT_EXIST	Selected positioner does not exist

-1038	PI_PARAMETER_FILE_ALREADY_OPENED	There is already a parameter file open. Close it before opening a new file
-1039	PI_PARAMETER_FILE_OPEN_ERROR	Could not open parameter file
-1040	PI_INVALID_CONTROLLER_VERSION	The version of the connected controller is invalid
-1041	PI_PARAM_SET_ERROR	Parameter could not be set with SPA-- parameter not defined for this controller!
-1042	PI_NUMBER_OF_POSSIBLE_WAVES_EXCEEDED	The maximum number of wave definitions has been exceeded
-1043	PI_NUMBER_OF_POSSIBLE_GENERATORS_EXCEEDED	The maximum number of wave generators has been exceeded
-1044	PI_NO_WAVE_FOR_AXIS_DEFINED	No wave defined for specified axis
-1045	PI_CANT_STOP_OR_START_WAV	Wave output to axis already stopped/started
-1046	PI_REFERENCE_ERROR	Not all axes could be referenced
-1047	PI_REQUIRED_WAVE_NOT_FOUND	Could not find parameter set required by frequency relation
-1048	PI_INVALID_SPP_CMD_ID	Command ID given to SPP or SPP? is not valid
-1049	PI_STAGE_NAME_ISNT_UNIQUE	A positioner name given to CST is not unique
-1050	PI_FILE_TRANSFER_BEGIN_MISSING	A uuencoded file transferred did not start with "begin" followed by the proper filename
-1051	PI_FILE_TRANSFER_ERROR_TEMP_FILE	Could not create/read file on host PC
-1052	PI_FILE_TRANSFER_CRC_ERROR	Checksum error when transferring a file to/from the controller
-1053	PI_COULDNT_FIND_PISTAGES_DAT	The PiStages.dat database could not be found. This file is required to connect a positioner with the CST command
-1054	PI_NO_WAVE_RUNNING	No wave being output to specified axis
-1055	PI_INVALID_PASSWORD	Invalid password
-1056	PI_OPM_COM_ERROR	Error during communication with OPM (Optical Power Meter), maybe no OPM connected
-1057	PI_WAVE_EDITOR_WRONG_PARAMNUM	WaveEditor: Error during wave creation, incorrect number of parameters
-1058	PI_WAVE_EDITOR_FREQUENCY_OUT_OF_RANGE	WaveEditor: Frequency out of range
-1059	PI_WAVE_EDITOR_WRONG_IP_VALUE	WaveEditor: Error during wave creation, incorrect index for integer parameter
-1060	PI_WAVE_EDITOR_WRONG_DP_VALUE	WaveEditor: Error during wave creation, incorrect index for floating point parameter
-1061	PI_WAVE_EDITOR_WRONG_ITEM_VALUE	WaveEditor: Error during wave creation, could not calculate value
-1062	PI_WAVE_EDITOR_MISSING_GRAPH_COMPONENT	WaveEditor: Graph display component not installed
-1063	PI_EXT_PROFILE_UNALLOWED_CMD	User profile mode: command is not allowed, check for required preparatory commands
-1064	PI_EXT_PROFILE_EXPECTING_MOTION_ERROR	User profile mode: first target position in user profile is too far from current position
-1065	PI_EXT_PROFILE_ACTIVE	Controller is (already) in user profile mode
-1066	PI_EXT_PROFILE_INDEX_OUT_OF_RANGE	User profile mode: block or data set index out of allowed range
-1067	PI_PROFILE_GENERATOR_NO_PROFILE	ProfileGenerator: No profile has been created yet

-1068	PI_PROFILE_GENERATOR_OUT_OF_LIMITS	ProfileGenerator: Generated profile exceeds limits of one or both axes
-1069	PI_PROFILE_GENERATOR_UNKNOWN_PARAMETER	ProfileGenerator: Unknown parameter ID in Set/Get Parameter command
-1070	PI_PROFILE_GENERATOR_PAR_OUT_OF_RANGE	ProfileGenerator: Parameter out of allowed range
-1071	PI_EXT_PROFILE_OUT_OF_MEMORY	User profile mode: out of memory
-1072	PI_EXT_PROFILE_WRONG_CLUSTER	User profile mode: cluster is not assigned to this axis
-1073	PI_UNKNOWN_CLUSTER_IDENTIFIER	Unknown cluster identifier
-1074	PI_INVALID_DEVICE_DRIVER_VERSION	The installed device driver doesn't match the required version. Please see the documentation to determine the required device driver version.
-1075	PI_INVALID_LIBRARY_VERSION	The library used doesn't match the required version. Please see the documentation to determine the required library version.
-1076	PI_INTERFACE_LOCKED	The interface is currently locked by another function. Please try again later.
-1077	PI_PARAM_DAT_FILE_INVALID_VERSION	Version of parameter DAT file does not match the required version. Current files are available at www.pi.ws .
-1078	PI_CANNOT_WRITE_TO_PARAM_DAT_FILE	Cannot write to parameter DAT file to store user defined positioner type.
-1079	PI_CANNOT_CREATE_PARAM_DAT_FILE	Cannot create parameter DAT file to store user defined positioner type.
-1080	PI_PARAM_DAT_FILE_INVALID_REVISION	Parameter DAT file does not have correct revision.
-1081	PI_USERSTAGES_DAT_FILE_INVALID_REVISION	User-defined positioner DAT file does not have correct revision.
-1082	PI_SOFTWARE_TIMEOUT	Timeout Error. Some lengthy operation did not finish within expected time.
-1083	PI_WRONG_DATA_TYPE	A function argument has an unexpected data type.
-1084	PI_DIFFERENT_ARRAY_SIZES	Length of data arrays is different.
-1085	PI_PARAM_NOT_FOUND_IN_PARAM_DAT_FILE	Parameter value not found in parameter DAT file.
-1086	PI_MACRO_RECORDING_NOT_ALLOWED_IN_THIS_MODE	Macro recording is not allowed in this mode of operation.
-1087	PI_USER_CANCELLED_COMMAND	Command cancelled by user input.
-1088	PI_TOO_FEW_GCS_DATA	Controller sent too few GCS data sets
-1089	PI_TOO_MANY_GCS_DATA	Controller sent too many GCS data sets
-1090	PI_GCS_DATA_READ_ERROR	Communication error while reading GCS data
-1091	PI_WRONG_NUMBER_OF_INPUT_ARGUMENTS	Wrong number of input arguments.
-1092	PI_FAILED_TO_CHANGE_CCL_LEVEL	Change of command level has failed.
-1093	PI_FAILED_TO_SWITCH_OFF_SERVO	Switching off the servo mode has failed.
-1094	PI_FAILED_TO_SET_SINGLE_PARAMETER_WHILE_PERFORMING_CST	A parameter could not be set while performing CST: CST was not performed (parameters remain unchanged).
-1095	PI_ERROR_CONTROLLER_REBOOT	Connection could not be reestablished after reboot.

-1096	PI_ERROR_AT_QHPA	Sending HPA? or receiving the response has failed.
-1097	PI_QHPA_NONCOMPLIANT_WITH_GCS	HPA? response does not comply with GCS2 syntax.
-1098	PI_FAILED_TO_READ_QSPA	Response to SPA? could not be received. Response to SPA? could not be received.
-1099	PI_PAM_FILE_WRONG_VERSION	Version of PAM file cannot be handled (too old or too new)
-1100	PI_PAM_FILE_INVALID_FORMAT	PAM file does not contain required data in PAM-file format
-1101	PI_INCOMPLETE_INFORMATION	Information does not contain all required data
-1102	PI_NO_VALUE_AVAILABLE	No value for parameter available
-1103	PI_NO_PAM_FILE_OPEN	No PAM file is open
-1104	PI_INVALID_VALUE	Invalid value
-1105	PI_UNKNOWN_PARAMETER	Unknown parameter
-1106	PI_RESPONSE_TO_QSEP_FAILED	Response to SEP? could not be received.
-1107	PI_RESPONSE_TO_QSPA_FAILED	Response to SPA? could not be received. Response to SPA? could not be received.
-1108	PI_ERROR_IN_CST_VALIDATION	Error while performing CST: One or more parameters were not set correctly.
-1109	PI_ERROR_PAM_FILE_HAS_DUPLICATE_ENTRY_WITH_DIFFERENT_VALUES	PAM file has duplicate entry with different values.
-1110	PI_ERROR_FILE_NO_SIGNATURE	File has no signature
-1111	PI_ERROR_FILE_INVALID_SIGNATURE	File has invalid signature
-1112	PI_ERROR_CANNOT_DETERMINE_ACTUAL_END_OF_TRAVEL_WHILE_PLATFORM_IS_MOVING	Cannot determine actual end of travel range while platform is moving.
-10000	PI_PARAMETER_DB_INVALID_STAGE_TYPE_FORMAT	PI positioner database: String containing positioner type and description has invalid format.
-10001	PI_PARAMETER_DB_SYSTEM_NOT_AVAILABLE	PI positioner database: Database does not contain the selected positioner type for the connected controller.
-10002	PI_PARAMETER_DB_FAILED_TO_ESTABLISH_CONNECTION	PI positioner database: Establishing the connection has failed.
-10003	PI_PARAMETER_DB_COMMUNICATION_ERROR	PI positioner database: Communication was interrupted (e.g. because database was deleted).
-10004	PI_PARAMETER_DB_ERROR_WHILE_QUERYING_PARAMETERS	PI positioner database: Querying data failed.
-10005	PI_PARAMETER_DB_SYSTEM_ALREADY_EXISTS	PI positioner database: System already exists. Rename positioner and try again.
-10006	PI_PARAMETER_DB_QHPA_CONTAINS_UNKNOWN_PAM_IDS	PI positioner database: Response to HPA? contains unknown parameter IDs.
-10007	PI_PARAMETER_DB_AND_QHPA_ARE_INCONSISTENT	PI positioner database: Inconsistency between database and response to HPA?.
-10008	PI_PARAMETER_DB_SYSTEM_COULD_NOT_BE_ADDED	PI positioner database: Positioner has not been added.
-10009	PI_PARAMETER_DB_SYSTEM_COULD_NOT_BE_REMOVED	PI positioner database: Positioner has not been removed.

-10010	PI_PARAMETER_DB_CONTROLLER_DB_PARAMETERS_MISMATCH	Controller does not support all positioner parameters stored in PI positioner database. No parameters were set.
-10011	PI_PARAMETER_DB_DATABASE_IS_OUTDATED	The version of PISTAGES3.DB positioner database is out of date. Please update via PIUpdateFinder. No parameters were set.
-10012	PI_PARAMETER_DB_AND_HPA_MISMATCH_STRICT	Mismatch between number of parameters present in positioner database and available in controller interface. No parameters were set.
-10013	PI_PARAMETER_DB_AND_HPA_MISMATCH_LOOSE	Mismatch between number of parameters present in positioner database and available in controller interface. Some parameters were ignored.
-10014	PI_PARAMETER_DB_FAILED_TO_SET_PARAMETERS_CORRECTLY	One or more parameters could not be set correctly on the controller.
-10015	PI_PARAMETER_DB_MISSING_PARAMETER_DEFINITIONS_IN_DATABASE	One or more parameter definitions are not present in positioner database. Please update PISTAGES3.DB via PIUpdateFinder. Missing parameters were ignored.

