Description of the Instruction Set

Venus

as implemented in the TANGO Controller

In der Murch 15
35579 Wetzlar
Germany
Tel.: +49/6441/9116-0
www.marzhauser.com

1. Table of Contents

2. Introduction

This manual is intended as technical reference for programmers of any software applications using the TANGO controller driven with the so-called Venus command set.
The TANGO controller can be configured for several different command languages. This manual describes the command set for language "Venus for TANGO", which is a superset of both interpreter languages Venus-1 and Venus-2. In general, the fundamental command construction and functions are compatible to these versions.

Examples

cal<CR>	calibrate all enabled axes (Venus-1)
2<SP>ncal<CR>	calibrate axis 2 only (Venus-2)
status<CR>	ask for the status of the controller
1.2<SP>3.4<SP>m<CR>	move absolute to x=1.2 and y=3.4 for a 2-axis controller

Please do not send more than 255 characters at once to the TANGO Controller, as the input buffer will overflow. To avoid this, it is recommended to request the status in between and wait for a value to be returned. Another solution is to activate the so called cts-handshake (available with Desktop RS232 and USB versions only). This will automatically halt the PC transmission for as long as the input buffer is full. The PC COM port then must be opened with hardware handshake on, too. Please refer the ***getcts*** and ***setcts*** commands for further description. Some of the most common commands are also available in abbreviations, to reduce communication time. Example: The command ***setjoyspeed*** is available as identical short form ***js.***

Secure speed limitation

The TANGO controller has a built-in security function, which reduces the maximum travel velocity to 10mm/s for as long as no initial ***cal*** and ***rm*** move is executed. This is to preserve the microscope stage from damage that could be caused by moving fast into its end positions. After calibrating the axis into its both limit switches, the travel velocity is no longer limited.
If this feature does not fit your purpose, the stage speed may be increased to up to 100mm/s at own risk. Please refer to the ***getsecvel*** and ***setsecvel*** command for further information.
The ***rm*** position information, once executed, can be kept for consecutive ***cal*** instructions if ***setkeeprm*** is set. This avoids that secvel will be applied after a new ***cal***, no new rm is required until power down or reset.

3. Instruction and Response Syntax Description

All instructions and parameters which are sent to the controller, as well as all feedbacks of the controller, are transferred as a sequence of ASCII characters. The connection can be established e.g. with a terminal program. The use of standard ASCII string communication is easy to understand and simplifies tracing of communication.
The controller does not distinguish between upper- and lower-case ASCII characters. While lower case might be preferred, the controller can also handle upper or camel case strings.
All floating-point numbers may contain a decimal point, commas are not supported.

Each parameter or instruction send to the controller may either be terminated by a carriage return <CR> or a blank <SP>. Both are supported and compatible with existing Venus-1 or Venus-2 installations.
<ETX> is used as special single character instruction, which is processed in a high priority manner. It stops automatic moves immediately at stop deceleration and clears the receive buffer.

Symbol	Name	Decimal	Hexadecimal	Keyboard	Binary
<ETX>	End of Text	3	0x03	Ctrl-C	00000011
<LF>	Line Feed	10	0x0A		00001010
<CR>	Carriage Return	13	0x0D		00001101
<SP>	Space	32	0x20	Blank	00100000

Commands and parameters may be separated or terminated by <SP> or <CR>. Both are equal:

command with one parameter	[parameter]<SP>[axis]<SP>[instruction]<CR>
or	[parameter]<SP>[axis]<SP>[instruction]<SP>

The controller response is always terminated by <CR><LF>:

response with one parameter	[parameter]<CR><LF>
response with two parameters	[parameter1]<SP>[parameter2]<CR><LF>

3.1. mode

The instruction ***mode*** sets the operation mode of the controller.
The TANGO controller only supports host mode (0).

```
Syntax:      [value] mode
Parameter:   [value] 0 = host mode
                     1 = terminal mode (not supported)
Response:    none

Examples:    0 mode (set host mode)
             1 mode (set terminal mode)
```

3.2. parameter

Some instructions require no parameter, while other require more than one. Many Venus-1 instructions, such as move and position instructions, require or return an amount of parameters that depends on the number of axes, as defined with setdim.

Whenever an instruction requires an [axis] parameter to specify a certain axis, the usual range is 1 to 4. Some instructions also allow an [axis] parameter of -1, usually to address all axes, or 0 for special access.

[axis] = index number	description
1	1st axis (X)
2	2nd axis (Y)
3	3rd axis (Z)
4	4th axis (A)
0	for access to some axis independent parameters
-1	to query or set all available axes, available with some instructions only

The following chapters describe each instruction in detail.

4. Stack Instructions

The Venus interpreter is based on a last in, first out parameter stack. All numbers get pushed on the stack when followed by either a <SP> or <CR>. The next instruction pops its required amount of parameters off the stack.

Remarks: The stack principle is unlike other command interpreters, where parameters and instruction form a unit and are processed together. Here, numbers always get pushed on the stack and the instruction fetches its individual required amount of numbers from there.

Parameters can remain on the stack if too many parameters were sent for an instruction, and over time fill up the stack. Then no further parameters are getting pushed on the stack and following instructions fetch the old parameters from the stack instead of the ones that were send with the instruction. This situation leads to unwanted, false behavior. Therefore, the recommendation is to

a) always provide exactly the required amount of command parameters at a time and ensure the stack is empty after its execution, and
b) Do not allow the stack to fill up due to instructions with a wrong number of parameters, possibly use the ***clear*** instruction at times to clear the stack.

The stack principle could be used to have parameters for several instructions already on the stack, and then call several instructions that fetch their parameters from the filled stack.

The stack size is typically 10 parameters. On overflow, no additional parameters get pushed on the stack and the error condition 1009 is signalled.

4.1. gsp

This instruction returns the number of actual parameters present on stack (stack pointer). After execution of any Venus instructions, the response to this ***gsp*** instruction should be zero. If this is not the case, this indicates that too many parameters have been sent with the instruction.

4.2. pop

This instruction removes the last parameter from the stack. The stack pointer is decremented by one.

4.3. clear

This instruction clears the stack and removes all parameters. The stack pointer is set to zero.
It can also be used frequently to prevent unused parameters to accumulate on the stack and causing stack overflow and erroneous behavior.

4.4. nclear

Same functionality as the ***clear*** instruction. Clearing a single axis stack is not supported by the TANGO.
This instruction clears the stack of all axes and removes all parameters. The stack pointer is set to zero.

5. Venus-1 vs. Venus-2 Instructions Cross Reference

The following table contains a cross reference list for Venus-1 and Venus-2 instructions. The TANGO controller provides all these instructions (both command sets can be used at the same time).

In general, the Venus-2 instructions are designed to control a single axis, while the Venus-1 was first designed to control up to three axes simultaneously. Valid short instructions are noted in brackets.

Venus-1	Venus-2	Description
Abort (Ctrl+C)	nabort (Ctrl+C)	abort automatic moves
move (m)	nmove (nm)	move absolute
rmove (rm)	nrmove (nr)	move relative
pos (p)	npos (np)	get position
setpos (sp)	setnpos (snp)	set position
getvel (gv)	getnvel (gnv)	get velocity
setvel (sv)	setnvel (snv)	set velocity
getaccel (ga)	getnaccel (gna)	get acceleration
setaccel (sa)	setnaccel (sna)	set acceleration
calibrate (cal)	ncalibrate (ncal)	calibrate
rangemeasure (rm)	nrangemeasure (nrm)	range measure
getlimit	getnlimit	get limit
setlimit	setnlimit	set limit
getcalvel	getncalvel	get calibration velocity
setcalvel	setncalvel	set calibration velocity
getrmvel	getnrmvel	get range measure velocity
setrmvel	setnrmvel	set range measure velocity
getjoyspeed	getnjoyspeed	get manual speed
setjoyspeed (js)	setnjoyspeed (njs)	set manual speed
joystick (j)	njoystick (nj)	enable/disable joystick
status (st)	nstatus (nst)	get state
version	nversion	get version

For Venus-1 style instructions the parameters depend on the value of ***getunit***.

For Venus-2 style instructions:

- Until Firmware 1.75, all Venus-2 style instructions used the fixed unit [mm], [mm/s] and [mm/s²] or depended on the axis unit.
- From Firmware 1.76, the Venus-2 style instructions, as several of the "n" instructions are also available in newer Venus-1 instruction sets, also depend on the ***getunit*** setting.

setunit defines the position and distance units per axis (1,2,3,4), while the unit for axis 0 (virtual 0-axis) defines the velocity and acceleration unit (one for all axes). Some parameters are even in revolutions/s independent of the selected unit 0 due to compatibility. There are options with **setting unit 0 to 9 or 10**, which turns all velocities **fix to mm/s** (**like Venus-2**), or to set it to -1, which makes all velocities and accelerations dependent on the individual axis unit. Please refer to ***getunit*** for further information.

6. Communication Interface Settings

The TANGO controller family provides several communication interfaces.
The following table shows which interface functions are supported by the different interface types.

	getbaud	setbaud	getcts	setcts
PCI/PCI-E Bus	⊘	⊘	✓	✓
USB	⊘	⊘	✓	✓
RS232	✓	✓	✓	✓
USB (BOB)	✓	✓	⊘	⊘

Ethernet	getipadr setipadr	getnetmask setnetmask	getgateway setgateway	getmacadr

6.1. getbaud

```
Syntax:     getbaud
Parameter:  none
Response:   {1200, 2400, 4800, 9600, 19200, 38400, 57600 or 115200}
Default:    57600
```

This instruction reads the serial communication transfer rate. The unit is bits per second [Bd]. However, this instruction only works if the serial connection is already established.

6.2. setbaud

```
Syntax:     [value] setbaud
Parameter:  {1200, 2400, 4800, 9600, 19200, 38400, 57600 or 115200}
Response:   none
Example:    57600 setbaud
```

The default baud rate of 57600 may be changed to the requirements of the specific application. However, this instruction works only if the serial connection is already established. This instruction changes the baud rate of the controller only. To re-establish communication, the corresponding COM Port of the PC must be opened with the same new baud rate afterwards. Then a ***save*** instruction may be sent to permanently store the new baud rate in the controller. For PCI, PCI-E and Desktop USB controllers the change of baud rate has no effect, it is always fixed internally to at least 4,125,000 baud, independent of the *setbaud*, *getbaud* parameters.

6.3. getcts

```
Syntax:     getcts
Parameter:  none
Response:   {0 or 1} (0 = hardware handshake off, 1 = hardware handshake on)
Default:    0
```

This instruction reads the current RTS/CTS hardware handshake enable state. The default setting is 0 (off).

6.4. setcts

```
Syntax:     [value] setcts
Parameter:  {0 or 1} (0 = hardware handshake off, 1 = hardware handshake on)
Response:   none
Example:    0 setcts
```

This instruction enables or disables the hardware handshake provided by some TANGO controllers.
0 disables the CTS hardware handshake, which is also the default setting and recommended for most applications. The PC COM Port must be reopened with the same setting. The setting can be stored by save.

6.5. getipadr

```
Syntax:     getipadr
Parameter:  none
Response:   [AAA].[BBB].[CCC].[DDD]
```

This instruction reads the current IP address of controllers with Ethernet interface.

6.6. setipadr

```
Syntax:     [AAA] [BBB] [CCC] [DDD] setipadr
Parameter:  4 Blocks of 0-255, separated by <SP>
Response:   none
Example:    192 168 1 162 setipadr
```

This instruction sets the IP address of controllers with Ethernet interface. A space separates the blocks.

6.7. getnetmask

```
Syntax:     getnetmask
Parameter:  none
Response:   [AAA].[BBB].[CCC].[DDD]
Default:    255.255.255.0
```

This instruction reads the current netmask of controllers with Ethernet interface.

6.8. setnetmask

```
Syntax:     [AAA] [BBB] [CCC] [DDD] setnetmask
Parameter:  4 Blocks of 0-255, separated by <SP>
Response:   none
Example:    255 255 255 0 setnetmask
```

This instruction sets the netmask of controllers with Ethernet interface. A space separates the blocks.

6.9. getgateway

```
Syntax:     getgateway
Parameter:  none
Response:   [AAA].[BBB].[CCC].[DDD]
```

This instruction reads the current default gateway setting of controllers with Ethernet interface.

6.10. setgateway

```
Syntax:     [AAA] [BBB] [CCC] [DDD] setgateway
Parameter:  4 Blocks of 0-255, separated by <SP>
Response:   none
Example:    192 168 1 254 setgateway
```

This instruction sets the default gateway of controllers with Ethernet interface. A space separates the blocks.

6.11. getmacadr

```
Syntax:     getmacadr
Parameter:  none
Response:   [NN]:[NN]:[NN]:[NN]:[NN]:[NN]
```

This instruction reads the unique MAC address of controllers with Ethernet interface.

7. Controller Informations

The instructions ***version***, ***nversion, identify, nidentify*** are provided for backward compatibility only.
The instructions ***getserialno, getso, tango*** report details about hardware and firmware versions.

7.1. version

```
Syntax:     version
Parameter:  none
Response:   3.61
```

7.2. nversion

```
Syntax:     [axis] nversion
Parameter:  axis
Response:   3.61
Example:    1 nversion
```

7.3. identify

```
Syntax:     identify
Parameter:  none
Response:   Corvus 1 361 1 0
```

7.4. nidentify

```
Syntax:     [axis] nidentify
Parameter:  axis
Response:   Pegasus 1 143 0 0
Example:    1 nidentify
```

7.5. getserialno

```
Syntax:     getserialno
Parameter:  none
Response:   [YY][WW][T][N][XXX]
            [YY]   year of manufacturing
            [WW]   week of manufacturing
            [T]    controller type identifier 0-9, A-Z
            [N]    in hardware available axes
            [XXX]  index number
Example:    193513017
```

The unique serial number of the TANGO controller, also including a type identifier.

7.6. getstageno

```
Syntax:     getstageno
Parameter:  none
Response:      [JJ][MM][TT][nn]
            or [JJ][MM][TT][nnn]
            or -------- if no stage serial number available
Examples:   getstageno ==> 170831005
            getstageno ==> ---------
```

The unique serial number of the microscope stage or connected axes.

7.7. tango

```
Syntax:     tango
Parameter:  none
Response:   [version string] [CR,LF] [tango serial number] [CR,LF]

Syntax:     ASCII string with controller type, firmware version, build date
            separated by a comma, and the serial number in a 2nd line:

            TANGO             Fixed string identifying the TANGO controller
                              and the appendix "-..." to identify the type:
            -DT               Desktop version (PCI based)
            -DT-S             Desktop version (PCI-S based)
            -DTe              Desktop version (PCIe based)
            -PCI              PCI card version (long PCI card)
            -PCI-S            Short PCI card version
            -PCIe             PCI Express card version
            -MINI             TANGO mini
            -MINI3            TANGO 3 mini
            -C                Motorized Stage with integrated Controller
            -I                TANGO integrale stage integrated controller
            -Desktop          TANGO Desktop HE         2nd generation DTe
            -I2               TANGO integrale          2nd generation MINI3
            -3-mini           TANGO 3 mini             2nd generation I
            -PCIE21           PCI-E card (PCI Express) 2nd generation PCIe


            Version 1.57      Firmware version number
            Apr 17 2012       Firmware build date
            12:12:02          Firmware build time

Example:    TANGO-DTe, Version 1.69, Mar  6 2018 , 15:52:19
            143513049
```

8. System Configuration

Many parameters can be stored permanently in the TANGO Controller, so they are available after each consecutive power on. When stored once, this reduces initialization overhead of the application software. Refer to the "save" instruction for further information.

8.1. save

```
Syntax:     save
Parameter:  none
Response:   none
```

This instruction stores your favourite parameter settings (like acceleration and speed) in a permanent and safe data area (also called non-volatile memory). These parameters will be taken by the controller after each consecutive reset or power on as default values.

8.2. restore

```
Syntax:     restore
Parameter:  none
Response:   none
```

This instruction overwrites the actual controller setting with parameters read from the non-volatile memory.

8.3. reset

```
Syntax:     reset
Parameter:  none
Response:   none
```

The controller is forced to perform a software reset. It is a restart similar to power on. Rebooting from reset will take more than 1 second, where the controller is not responding. There is no reply to a software reset. So for knowing if the controller is rebooted and ready, it may be necessary to poll data until it responds again, and USB connections might require a reconnect in case the port disappears (2nd generation TANGOs with USB).

8.4. getpowerup

```
Syntax:     getpowerup
Parameter:  none
Response:   current power up mode
Example:    getpowerup (assume response 2 => "calibrate" and "joystick off")
```

The instruction ***getpowerup*** reads the current power up mode. It is applied to all available axes (***getdim***).
The response is a bit combination:

Response		Description
	0	No power up functionality, last saved joystick mode is used
bit 2^0	1	Joystick on after power up or reset
bit 2^1	2	Calibration move after power up or reset
bit 2^2	4** (6)	Range Measure move after power up or reset, ** only to be used together with calibration option: cal+rm = 2+4 = 6
bit 2^3	8 (14)	Random move, combination with cal+rm required: 2+4 + 8 = 14
bit 2^4	16	Performs Calibration and Range Measure, then travels to the zero position
bit 2^5	32	Enables closed loop after power up or reset

8.5. setpowerup

```
Syntax:     [value] setpowerup
Parameter:  required power up mode (refer table above for getpowerup)
Response:   none
Example:    1 setpowerup (enable joystick after power up)
            3 setpowerup (enable joystick and perform calibration after power up)
```

The instruction ***setpowerup*** causes the controller to automatically perform the desired behaviour on all active axes (***getdim***) after power up or reset. Power up instructions may be combined, but not all combinations are allowed or make sense.
For a complete list of options please refer to the ***getpowerup*** description.

8.6. getipreter

```
Syntax:     getipreter
Parameter:  none
Response:   certainly 2 here only
```

This instruction reads the number of the actual selected interpreter. The response 2 indicates the Venus instruction set is set active as described in this manual.

8.7. setipreter

```
Syntax:     [value] setipreter
Parameter:  {1 or 2}
Response:   none
Example:    2 setipreter
```

This instruction selects the required interpreter.

instruction	Description
1 setipreter	switch from Venus to native instruction set (refer separate manual)
!ipreter 2	switch from native to Venus instruction set (see this manual)

9. Motor Configuration

The controller is adaptable for different motors with the following set of instructions.

9.1. gi

```
Syntax:     [axis] gi
Parameter:  [axis] 1,2,3,4
Response:   motor current in unit Ampere [A]
Example:    2 gi (assume response 0.8 => 0.8 A motor current of axis 2)
```

This instruction reads the programmed motor current in unit Ampere [A], as set by ***si***.

9.2. si

```
Syntax:     [value] [axis] si
Parameter:  [value] is motor current in [A]
            [axis] 1,2,3,4
Response:   none
Example:    0.8 1 si (set motor current 0.8 A for axis 1)
```

This instruction sets the required motor current. Please read the motor data sheet for details and do not exceed the maximum ratings, since this may damage the motor permanently. (This instruction replaces setumotmin and setumotgrad, which are not used by the TANGO.)

9.3. getpolepairs

```
Syntax:     [axis] getpolepairs
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   integer
Example:    2 getpolepairs (reads axis 2 number of motor pole pairs)
Reply:      50             (here a 200 steps motor is configured)
```

The instruction ***getpolepairs*** reads the controller settings for the motor pole pairs of the asked axis.

9.4. setpolepairs

```
Syntax:     [value] [axis] setpolepairs
Parameter:  [value] is the number of the motor pole pairs (as integer)
            [axis]  1,2,3,4 or -1 to set all axes with one parameter
Response:   none
Example:    50 1 setpolepairs   (adapts axis 1 to a motor with 200 steps/rev)
            100 -1 setpolepairs (set all axes to a motor with 400 steps/rev)
```

The instruction ***setpolepairs*** adapts the controller to the required number of motor pole pairs for the requested axis. For clarification: A 2-phase stepper motor with 200 steps/rev (1.8°) has 50 pole pairs. And one with 400 steps/rev (0.9°) has 100 pole pairs.

9.5. getmotiondir

```
Syntax:     [axis] getmotiondir
Parameter:  [axis] 1,2,3 or 4
Response:   0 = default motor direction
            1 = reversed motor direction
Example:    2 getmotiondir (read direction of 2nd axis)
```

The instruction ***getmotiondir*** reads the motor direction of the specified axis.

9.6. setmotiondir

```
Syntax:     [direction] [axis] setmotiondir
Parameter:  [axis]      1,2,3 or 4
            [direction] 0 = default motor/axis direction
                        1 = reversed motor/axis direction
Response:   none
Example:    0 2 setmotiondir (set axis 2 to default direction)
```

The instruction ***setmotiondir*** sets the motor direction of the specified axis.
The the **cal** and **rm** limit switch assignment is changed automatically.

10. Controller States and Error Messages

The two instructions ***geterror*** and ***getstatus*** are useful to determine, if an unusual event has happened or the last instruction was executed. The response to ***ge*** and ***st*** reflects the actual controller state.

10.1. geterror (ge)

```
Syntax:     geterror or ge
Parameter:  none
Response:   error code
```

The instruction ***geterror*** reads the current controller error state, which indicates the last occurred error. The error message is deleted after the instruction is executed. Please refer chapter "Table of Error Numbers" for possible values and description.
This instruction can also be used as a blocking instruction in order to wait for completion of a move.

10.2. getnerror (gne)

```
Syntax:     [axis] getnerror or gne
Parameter:  [axis] 1,2,3,4
Response:   error code
```

The instruction ***getnerror*** reads the current controller error state, which indicates the last occurred error. The error message is deleted after the instruction is executed. Please refer chapter "Table of Error Numbers" for possible values and description.
This instruction can also be used as a blocking instruction in order to wait for completion of a move.
Implementation is of limited compatibility, no blocking for multiple axes, no error for a single axis available.

10.3. status (st)

```
Syntax:     status or st
Parameter:  none
Response:   actual controller status (integer in range of {0..511})
Example:    st --> 2 (axes are idle and joystick is enabled)
```

The instruction ***status*** reads the current controller status. The replied value reflects the operating state of the controller in a binary coded decimal representation. To decode the states correctly it is necessary to use a bit mask. Greyed status bits are currently not supported.

Bit	Decimal	0 indicates	1 indicates
D0	1	idle / move completed	controller executes a move
D1	2	manual mode (HDI) is not active	manual mode is active
D2	4	button A not pressed	button A pressed
D3	8	no function	no function
D4	16	speed mode is not active	speed mode is active
D5	32	position out of target window	position within the target window
D6	64	stop signal not active or not enabled	axes stopped by stop signal (setinfunc)
D7	128	motor driver is enabled	motor driver is disabled
D8	256	Joystick button not pressed	Joystick button pressed

10.4. nstatus (nst)

```
Syntax:     nstatus or nst
Parameter:  axis
Response:   actual axis status (integer in range of {0..255})
Example:    1 nst --> 2 (axis 1 is idle and joystick is enabled)
```

The instruction ***nstatus*** reads the current axis status. The replied value reflects the operating state of the controller axis in a binary coded decimal representation. To decode the states correctly it is necessary to use a bit mask. Greyed status bits are currently not supported.

Bit	Decimal	0 indicates	1 indicates
D0	1	idle / move completed	axis executes a move
D1	2	manual mode (HDI) is not active	manual mode is active
D2	4	no machine error	machine error
D3	8	no function	no function
D4	16	no function	no function
D5	32	position out of target window	position within the target window
D6	64	stop signal not active or not enabled	axes stopped by stop signal (setinfunc)
D7	128	motor driver is enabled	motor driver is disabled

11. General Adjustments

With the following instructions the parameters of the controller are widely scalable to the given mechanic construction and to customer requirements. The controller is adaptable to all the requested requirements.

11.1. getunit

```
Syntax:     [axis] getunit
Parameter:  [axis] 0,1,2,3,4 or -1 (all axes with virtual 0-axis listed first)
Response:   integer in range of {-1..10}
Example:    2 getunit (read unit of axis 2)
```

The instruction ***getunit*** reads the unit of input and output parameters concerning, position, distance, velocity and acceleration.

Positions and distances:
Concerning the position and distance parameters, the unit can be individually assigned for each axis.
While the velocity unit is defined one for all axes here through the setting of the "virtual axis" number 0:

Velocity and acceleration:
The unit index number 0 (virtual 0-axis) specifies the unit of velocity and acceleration for all axes.
Exceptions are ***setcalvel, setncalvel, setrmvel, setnrmvel, setrefvel, setnrefvel*** and the ***speed*** instruction, which use the fixed ***rev/s*** unit for backward compatibility. But:
The virtual 0-axis unit can also be set to 9, 10 or -1 in order to achieve a more unified behavior:
At unit 0 = 9 and 10, all velocity and acceleration units are in **mm/s and mm/s²**, like the Venus-2 interpreter.
At unit 0 = -1, all velocity and acceleration **units** are taken **from the individual axis units**.
Only the virtual 0-axis accepts the unit parameter -1 aside the other unit options 0 to 10.

The possible values for unit are:

Value	unit	
0	Microsteps	The unit ***Microsteps*** is emulated for compatibility with older controllers. With this unit the resolution of the controller is reduced, e.g. to 1 Microstep = 1/40000 revolution. The microstep resolution is not necessarily fixed to 40000, it can be set as required. Please refer to the instruction ***setusteps*** and ***getusteps***.
1	µm	
2	mm	
3	cm	
4	m	
5	inch	
6	mil (1/1000 inch)	
7	0..360°	
8	revolutions	
9	mm	
10	µm	

11.2. setunit

```
Syntax:     [value] [axis] setunit
Parameters: [value] in range of {-1, 0..10} (for description see getunit)
Response:   none
Example:    2 1 setunit (set unit of axis 1 to mm)
```

The instruction ***setunit*** sets the individual axis units concerning position, and Axis 0 (virtual 0-axis) sets the unit for velocity and acceleration of all axes. Please refer to ***getunit*** for a detailed description.
For best Venus-2 compatibility, set all axis units to mm (2) and the virtual 0-axis unit to 9 (=default).

11.3. getusteps

```
Syntax:     getusteps
Parameter:  none
Response:   integer [micro steps/revolution]
Example:    getusteps (read actual setting of micro steps)
```

The instruction ***getusteps*** reads the actual number of micro steps / revolution, as used in microsteps unit mode. The TANGO default is 819200 micro steps per revolution (for 1.8° motors). In case your application is designed to work with a different value, you may adapt the TANGO to your requirements with setusteps.

11.4. setusteps

```
Syntax:     [value] setusteps
Parameters: value = required microsteps/rev.
Response:   none
Example:    40000 setusteps
```

The instruction ***setusteps*** defines the required value of microsteps for the microsteps unit mode. The TANGO default is 819200 micro steps per revolution (for 1.8° motors). In case your application is designed to work with a different value, e.g. 40000 or 51200, setustep allows to adapt the TANGO to those requirements.

11.5. getdim

```
Syntax:     getdim
Parameter:  none
Response:   integer in range of {1..4}
Example:    getdim (read actual setting of dimension)
```

The instruction ***getdim*** reads the actual setting of dimension of all input and output parameters related to length, e.g. position or move instructions.

Please consider that several instructions require a number of parameters that exactly meet the number of here defined axes. Providing less or more parameters than the number of axes will lead to stack underflow or overflow.

The possible values for dimension are:

Value	expected or replied axis parameters
1	[axis1]
2	[axis1] [axis2]
3	[axis1] [axis2] [axis3]
4	[axis1] [axis2] [axis3] [axis4]

11.6. setdim

```
Syntax:     [value] setdim
Parameters: value in range of 1 to 4, description see table above
Response:   none
Example:    2 setdim (set dimension, the number of used axes, to 2)
```

The instruction ***setdim*** defines how many parameters the controller expects or replies for dimension dependent instructions (such as pos and move). The instruction ***setdim*** does not switch on or off any axes.

11.7. getpdisplay

```
Syntax:     [axis] getpdisplay
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   [value1] (number of digits before the decimal point)
            [value2] (number of digits after the decimal point)
Example:    2 getpdisplay (assume response 9 3 => pos format is "__345.789")
```

The instruction ***getpdisplay*** (Get Position Display) returns the actual position format. The response are two integer numbers. The first is the number of digits before the decimal point. The second is the number of digits after the decimal point.

11.8. setpdisplay

```
Syntax:     [value1] [value2] [axis] setpdisplay
Parameter:  [value1] is the number of digits before the decimal point
            [value2] is the number of digits after the decimal point
Response:   none
Example:    10 4 1 setdisplay (set format 10.4 for pos response)
```

The instruction ***setpdisplay*** (Set Position Display) defines the format of the response to instruction ***pos***. The first parameter specifies the number of digits before the decimal point. The second parameter specifies the number of digits after the decimal point. NOT FULLY SUPPORTED AND CAN CURRENTLY NOT BE STORED YET IN THE TANGO.

11.9. getpitch

```
Syntax:     [axis] getpitch
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   floating point number in [mm]
Example:    2 getpitch (reads the pitch of axis 2)
Reply:      2.000000   (pitch value of axis 2, here 2mm)
```

The instruction ***getpitch*** reads the lead screw pitch setting of the specified axis.

11.10. setpitch

```
Syntax:     [value] [axis] setpitch
Parameter:  [value] is spindle pitch (in mm as a floating point number)
            [axis]  is 1,2,3,4 or 0 for the virtual axis pitch
Response:   none
Example:    4 1 setpitch    (set pitch to 4   [mm] for axis 1)
            0.1 3 setpitch  (set pitch to 0.1 [mm] for axis 3)
```

The instruction ***setpitch*** adapts the controller to the required lead screw pitch of the specified axis.
The unit is always in mm per revolution.
Corvus: The virtual axis 0 pitch is used to calculate setcalvel, setrmvel, setrefvel, setncalvel in rev/s.

11.11. getaccel (ga)

```
Syntax:     getaccel or ga
Parameter:  none
Response:   floating point number, the unit depends on 0 getunit
Example:    ga (reads acceleration, only one value for all axes)
```

The instruction ***getaccel*** reads the general acceleration taken for automatic moves. The answer depends on the actual setting of ***unit 0***. Assume the instruction ***0 getunit*** responds with 2, then the unit of acceleration will be in [mm/s²].

11.12. setaccel (sa)

```
Syntax:     [value] setaccel or sa
Parameter:  value is acceleration (as a floating point number)
Response:   none
Example:    0.2 sa (sets accelerations to 0.2, the unit depends on 0 getunit)
```

The instruction ***setaccel*** defines the acceleration for automatic moves. One parameter sets all axes.
The unit depends on the setting of ***unit 0***. To set individual accelerations per axis, please use ***setnaccel***.

11.13. getnaccel (gna)

```
Syntax:     [axis] getnaccel or gna
Parameter:  axis 1,2,3,4 or -1 for all axes
Response:   floating point number in [mm/s²]
Example:    2 gna (reads acceleration of axis 2)
```

The instruction ***getnaccel*** reads the acceleration of the specified axis taken for automatic moves.
The unit is in [mm/s²].

11.14. setnaccel (sna)

```
Syntax:     [value] [axis] setnaccel or sna
Parameter:  value is acceleration (as a floating point number)
Response:   none
Example:    200 2 sna (sets acceleration for axis 2 to 200 [mm/s²])
```

The instruction ***setnaccel*** defines the acceleration for the specified axis for automatic moves.
The unit is in [mm/s²].

11.15. getnstopdecel

```
Syntax:     [axis] getnstopdecel
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   floating point number in [mm/s²]
Example:    2 getnstopdecel (reads the stop deceleration of axis 2)
```

The instruction ***getnaccel*** reads the stop acceleration of the specified axis for nabort and limit switches.
The unit is in [mm/s²].

11.16. setnstopdecel

```
Syntax:     [value] [axis] setnstopdecel
Parameter:  [value] is acceleration as a floating point number in [mm/s²]
Response:   none
Example:    1000.0 2 setnstopdecel (sets the stop deceleration of axis 2 to 1m/s²)
```

11.17. getaccelfunc

```
Syntax:     getaccelfunc
Parameter:  -
Response:   0 or 1
Example:    getaccelfunc (reads acceleration function)
```

The instruction ***getaccelfunc*** reads the acceleration function. It is recommended to use ***getnaccelfunc***.

11.18. setaccelfunc

```
Syntax:     [value] setaccelfunc
Parameter:  [value] 0 = linear acceleration
                    1 = sin² acceleration (s-curve)
Response:   none
Example:    1 setaccelfunc (sets acceleration function for all axes to sin²)
```

The instruction ***setaccelfunc*** defines the acceleration function for all axes for automatic moves.

11.19. getnaccelfunc

```
Syntax:     [axis] getnaccelfunc
Parameter:  axis
Response:   0 or 1
Example:    2 getnaccelfunc (reads acceleration function of axis 2)
```

The instruction ***getnaccelfunc*** reads the selected acceleration function of the specified axis for automatic moves.

11.20. setnaccelfunc

```
Syntax:     [value] [axis] setnaccelfunc
Parameter:  [value] 0 = linear accelerations
                    1 = sin² acceleration (s-curve)
            [axis]  1,2,3,4
Response:   none
Example:    1 2 setnaccelfunc (sets acceleration function for axis 2 to sin²)
```

The instruction ***setnaccelfunc*** defines the acceleration function for the specified axis for automatic moves.

11.21. getvel (gv)

```
Syntax:     getvel or gv
Parameter:  none
Response:   floating point number
Example:    gv (reads the velocity)
```

The instruction ***getvel*** reads the velocity. The answer depends on the actual setting of ***unit 0***.
Assume instruction ***0 getunit*** responds with 2, then the unit of velocity will be in [mm/s].
To read individual velocities, please use ***getnvel***.

11.22. setvel (sv)

```
Syntax:     [value] setvel or sv
Parameter:  value is the velocity for automatic moves (floating point number)
Response:   none
Example:    20 sv (sets the velocity 20, the unit depends on "0 getunit")
```

The instruction ***setvel*** defines the velocity for automatic moves. One parameter applies to all axes.
The unit is defined by ***setunit*** on the virtual axis 0. To set individual velocities, please use ***setnvel***.
The HDI (joystick etc.) velocities must be set with the ***setjoyspeed*** and ***setjoybspeed*** instructions.

11.23. getnvel (gnv)

```
Syntax:     [axis] getnvel or gnv
Parameter:  axis
Response:   floating point number
Example:    2 gnv (reads the velocity of axis 2, e.g. 10.000000)
```

The instruction ***getnvel*** reads the velocity of the selected axis.
The answer depends on the unit of the corresponding axis, see ***[axis] getunit***.

11.24. setnvel (snv)

```
Syntax:     [value] [axis] setnvel or snv
Parameter:  value is the velocity for automatic moves (floating point number)
Response:   none
Example:    0.5 3 snv (sets the velocity for axis 3 to 0.5)
```

The instruction ***setnvel*** defines the velocity for automatic moves for the selected axis.
The parameter depends on the unit of the corresponding axis, see ***[axis] getunit***.

11.25. getsecvel

```
Syntax:     getsecvel
Parameter:  none
Response:   Currently used secure velocity [1 to 100 mm/s]
Example:    getsecvel (read the secure velocity limitation)
```

The instruction ***getsecvel*** reads the security speed limitation. This value is used as limit for calculations until the axes are calibrated and range measured (***cal***, ***rm***). It prevents the axis from mechanical damage as long as the controller does not know the mechanical limits. The velocity unit is always mm/s.

11.26. setsecvel

```
Syntax:     [value] setsecvel
Parameter:  secure speed limitation in mm/s as floating point, 0.000001 … 100
Response:   none
Example:    20 setsecvel (limit the axes speed to 20 mm/s)
```

The instruction ***setsecvel*** defines the secure speed limitation until ***cal*** and ***rm*** are executed. The velocity unit is always mm/s and does not depend on the ***unit*** state. It prevents the axis from mechanical damage as long as the controller does not know the mechanical limits.

11.27. getnsecvel

```
Syntax:     [axis] getnsecvel
Parameter:  axis index is 1,2,3,4 or -1 for all axes (axes depend on getdim)
Response:   Currently used secure velocity of the axis [1 to 100 mm/s] float
Example:    1 getnsecvel (read the secure velocity limitation of the X-axis)
```

The instruction ***getnsecvel*** reads the security speed limitation of the specified axis. This value is used as limit for calculations until the axes are calibrated and range measured (***cal***, ***rm***). The velocity unit is always mm/s and does not depend on the ***unit*** state. It prevents the microscope stage from mechanical damage as long as the controller does not know the mechanical limits.

11.28. setnsecvel

```
Syntax:     [value] [axis] setnsecvel
Parameter:  secure speed limitation in [mm/s] as floating point
            axis index is 1,2,3 or 4
Response:   none
Example:    5.5 3 setnsecvel (limit the X-axis speed to 5.5 mm/s)
```

The instruction ***setnsecvel*** defines the secure speed limitation until ***cal*** and ***rm*** are executed of the specified single axis. The velocity unit is always mm/s and does not depend on the ***unit*** state. It prevents the microscope stage from mechanical damage as long as the controller does not know the mechanical limits.

11.29. getaxis

```
Syntax:     [axis] getaxis
Parameter:  axis index is 1,2,3,4 or -1 for all axes
Response:   current state of asked axis
Example:    2 getaxis (read the axis state of axis 2, = Y axis)
```

The instruction ***getaxis*** reads the current axis state. The response is either 1, 0 or -1.
Not available axes return -1. Disabled axes (0, -1) are excluded from move, speed and cal/rm.

Response	Description
1	enabled
0	disabled (with motor current on)
-1	disabled (with motor current off)

11.30. setaxis

```
Syntax:     [value] [axis] setaxis
Parameter:  value is either 1,0 or -1 (refer table above)
Response:   none
Example:    1 3 setaxis (enable axis 3)
```

The instruction ***setaxis*** enables, disables, or switches off the selected axis.
Disabled axes (0, -1) are excluded from move, speed and cal/rm.

12. Limit Switch Instructions (Hardware and Software)

The instruction set provides hardware limits as well as definable software limits for each axis. Hardware limits protect the axes.

12.1. getsw

```
Syntax:     [axis] getsw
Parameter:  axis index 1,2,3 or 4
Response:   [cal switch (E0)] [rm switch (EE)]
Example:    2 getsw (assume response 0 0 => both are normal open)
```

response	description
0	switch type = normal open
1	switch type = normal close
2	hardware limit switch is ignored

The instruction ***getsw*** reads the actual settings for the limit switches of the requested axis.

12.2. setsw

```
Syntax:     [type] [switch] [axis] setsw
Parameter:  [type] see table above and [switch] see table below
Response:   none
Example:    2 1 3 setsw (ignore rm switch of axis 3)
```

[switch]	description
0	cal switch (E0)
1	rm switch (EE)

The instruction ***setsw*** sets the required type for the hardware limit switches.

12.3. getswst

```
Syntax:     [axis] getswst
Parameter:  axis index 1,2,3 or 4
Response:   [cal switch (E0) status] [rm switch (EE) status]
Example:    2 getswst (assume response 0 1 => rm switch of axis 2 is crossed)
```

The instruction ***getswst*** reads the actual state of the hardware limit switches.

12.4. setkeeprm

```
Syntax:     [index] [axis] setkeeprm
Parameter:  [index] 0 or 1, [axis] 1,2,3 or 4
Response:   none
Example:    1 3 setkeeprm (enable keeprm functionality for axis 3)
```

The instruction ***setkeeprm*** sets the required behavior for the keeprm mode per axis (default=0).
The keeprm mode remembers the axis length after ***cal***+***rm*** and restores it, if a ***cal*** without *rm* is executed later.
So the axis limit remains and the secvel is not applied, a new rm is not required to save time.

12.5. getkeeprm

```
Syntax:     [axis] getkeeprm
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   [index] 0 or 1
Example:    2 getswst (assume response 0 1 => rm switch of axis 2 is crossed)
```

The instruction ***getkeeprm*** reads the actual enable state of the keeprm mode.

12.6. getlimit

```
Syntax:     getlimit
Parameter:  none
Response:   [lower limit] [upper limit]<CR><LF>
            The number of responses depends on getdim.
Example:    getlimit (read the position limits)
        --> -1000 1000      (assume getdim = 1)
        --> -1000 1000      (assume getdim = 2)
            -1000 1000
        --> -1000 1000      (assume getdim = 3)
            -1000 1000
            -1000 1000
```

The instruction ***getlimit*** reads the maximum allowed positioning range. After executing a ***cal*** and ***rm*** sequence, the limits are set to the available travel range. They can be narrowed by the ***setlimit*** instruction. The number of returned values depends on ***getdim*** (two for each axis). Each pair of lower/upper limits is separated by a <CR><LF>. The unit of the returned values depends on ***getunit***.

12.7. setlimit

```
Syntax:     [lower1] [lower2] [lower3] [upper1] [upper2] [upper3] setlimit
Parameter:  lower or upper software limit
Response:   none
Example:    set the limit of all axes to +-1000 (mm)
            -1000 1000 setlimit                          (assume getdim = 1)
            -1000 -1000 1000 1000 setlimit               (assume getdim = 2)
            -1000 -1000 -1000 1000 1000 1000 setlimit    (assume getdim = 3)
```

The instruction s***etlimit*** sets the maximum allowed positioning range. The number of required parameters depends on ***getdim***. There are two parameters for each axis. The parameters must be sent as: first all lower limits, then all upper limits (and not alternating lower/upper). The unit depends on ***getunit***.

12.8. getnlimit

```
Syntax:     [axis] getnlimit
Parameter:  axis
Response:   [lower limit] [upper limit]<CR><LF>
Example:    2 getnlimit (read the allowed positioning range of axis 2 in [mm])
```

The instruction ***getnlimit*** reads the maximum allowed positioning range of a single axis. Usually a ***ncal*** and ***nrm*** sequence is used to detect both hardware limits. If either only one or no limit switch is mounted, then the response will reflect the user definable software limits instead. The unit depends on ***getunit***.

12.9. setnlimit

```
Syntax:     [lower] [upper] [axis] setnlimit
Parameter:  lower software limit, upper software limit, axis
Response:   none
Example:    -1000 1000 2 setnlimit
```

The instruction ***setnlimit*** sets the maximum allowed positioning range for one axis. This is useful if either only one or no limit switch is mounted. The unit depends on ***getunit***.

13. Calibration and Range Measure Instructions

After each power on or ***reset*** instruction the actual position of all axes is assumed as zero. Also, the travel speed is limited as defined by ***getsecvel*** until the axes are calibrated and range measured. This prevents mechanical hardware collisions, even if the limit switches are close to the mechanical end.
The user may run a calibration (***cal*** or ***ncal***) followed by a range measure (***rm*** or ***nrm***), if the system is equipped with the corresponding limit switches. The cal position becomes the new zero position. The speed during calibration can be adjusted with ***setncalvel*** and ***setnrmvel***.
If ***getcalswdist*** and ***getrmswdist*** are zero, then the cal and rm position is very close before the limit switches (about 0.1mm). Switches with low actuate/release hysteresis might require an extra position offset to prevent unintentional actuation when traveling at the ends of the axis. This offset (e.g. 1mm) can be defined with ***setcalswdist*** and ***setrmswdist***.

13.1. calibrate (cal)

```
Syntax:     calibrate or cal
Parameter:  none
Response:   none
```

This instruction moves all currently enabled axes in negative direction towards lower positions, until the calibration limit switch E0 is detected. It then moves in positive direction out of the switch. If calswdist=0, the axis will stop moving as soon as the limit switch E0 is released and set the position to 0.0. If calswdist>0, the axes will continue moving until this distance, and then set the position to 0. The final position of each axis is also taken as its lower software limit.

13.2. ncalibrate (ncal)

```
Syntax:     [axis] ncalibrate or ncal
Parameter:  axis 1,2,3,4 or -1 to calibrate all active axes
Response:   none
Example:    2 ncal (calibrate axis 2)
```

This instruction moves the selected axis in negative direction towards lower positions, until the limit switch E0 is detected. It then moves it in positive direction out of the switch. If calswdist=0, the axis will stop moving as soon as the limit switch E0 is released and set the position to 0. If calswdist>0, the axis will continue moving until this distance, and then set the position to 0. The final position is also taken as lower software limit.

13.3. rangemeasure (rm)

```
Syntax:     rangemeasure or rm
Parameter:  none
Response:   none
```

This instruction moves all currently enabled axes in positive direction towards higher positions, until the limit switch EE is detected. It then moves in negative direction towards lower positions. If rmswdist=0, the axes will stop moving, as soon as the limit switch EE is released. If rmswdist>0, the axes will continue moving until this distance. The final position is taken as upper software limit.

13.4. nrangemeasure (nrm)

```
Syntax:     [axis] nrangemeasure or nrm
Parameter:  axis 1,2,3,4 or -1 to range measure all active axes
Response:   none
Example:    2 nrm (range measure axis 2)
```

This instruction moves the selected axis in positive direction towards higher positions, until the limit switch EE is detected. It then moves it in negative direction towards lower positions. If rmswdist=0, the axis will stop moving as soon as the limit switch EE is released. If rmswdist>0, the axis will continue moving until this distance. The final position is taken as upper software limit.

13.5. getcalswdist

```
Syntax:     [axis] getcalswdist
Parameter:  axis
Response:   actual calibration offset
Example:    2 getcalswdist (get cal offset position of axis 2)
```

This instruction reads the current calibration offset. The unit depends on the current value of instruction ***getunit***.

13.6. setcalswdist

```
Syntax:     [value] [axis] setcalswdist
Parameter:  value
Response:   none
Example:    0.3 2 setcalswdist (set 0.3 cal offset of axis 2)
```

This instruction specifies an extra offset position above the limit switch E0 (towards higher positions) where to zero the axis and take this position as lower software limit. The unit depends on the current value of instruction ***getunit***.

13.7. getrmswdist

```
Syntax:     [axis] getrmswdist
Parameter:  axis
Response:   actual range measure offset
Example:    2 getrmswdist (get rm offset position of axis 2)
```

This instruction reads the current range measure offset. The unit depends on the current value of instruction ***getunit***.

13.8. setrmswdist

```
Syntax:     [value] [axis] setrmswdist
Parameter:  value
Response:   none
Example:    0.3 2 setrmswdist (set 0.3 rm offset at axis 2)
```

This instruction specifies an extra offset position below the limit switch EE (towards lower positions) where to define the upper software limit. The unit depends on the current value of instruction ***getunit***.

13.9. getncaltimeout

```
Syntax:     [axis] getncaltimeout
Parameter:  axis
Response:   value<CR><LF> axis timeout for cal and rm in seconds
Example:    2 getncaltimeout  (read timeout of axis 2)
            -1 getncaltimeout (read timeout of all axes)
```

This instruction reads the timeout for cal and rm instructions in seconds.

13.10. setncaltimeout

```
Syntax:     [value] [axis] setncaltimeout
Parameter:  value in [s], 0 to 120
Response:   none
Example:    60 1 setncaltimeout (set timeout of axis 1)
```

This instruction defines the timeout for cal and rm instructions in seconds.

13.11. getcalvel

```
Syntax:     getcalvel
Parameter:  none
Response:   value1<CR><LF> value2<CR><LF> floating point numbers
Example:    getcalvel (get cal velocity and cal retract velocity)
```

This instruction reads the current calibration speeds. Value1 is the speed towards the lower limit switch E0. Value2 is the speed used during retraction from lower limit switch E0. There is only one pair of values for all axes. The unit is per default **rev/s** but can be turned to mm/s by setting the virtual 0-axis unit to 9 or -1.

13.12. setcalvel

```
Syntax:     [value] [index] setcalvel
Parameter:  [value] floating point number (larger than 0 to 20 mm/s)
            [index] 1=towards, 2=out of switch
Response:   none
Example:    10 1 setcalvel 0.5 2 setcalvel
```

This instruction sets the calibration speeds for cal. Index=1 sets the speed towards the lower limit switch E0. Index=2 sets the speed used during retraction from lower limit switch. There is only one pair of values for all axes. The unit is per default **rev/s** but can be turned to mm/s by setting the virtual 0-axis unit to 9 or -1. Values must be larger than 0 and below or, when e.g. entered in rev/s, result in below 20 mm/s.

13.13. getncalvel

```
Syntax:     [axis] getncalvel
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   value1<CR><LF>value2<CR><LF> (2 floating point numbers per axis)
Example:    2 getncalvel (get cal velocity and cal retract velocity of axis 2)
Reply:      10.000000
            0.500000
```

This instruction reads the current calibration velocities for the cal instruction for individual axes.
Value1 is the speed towards the lower limit switch E0. Value2 is the speed taken during retraction from lower limit switch E0. Two lines are replied per axis, as each value is terminated by <CR><LF>.

The unit is per default **rev/s**, for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.14. setncalvel

```
Syntax:     [value] [index] [axis] setncalvel
Parameter:  [value] is the velocity as floating point number
            [index] is the parameter number: 1 (towards switch) or 2 (out of)
            [axis]  is 1,2,3,4
Response:   none
Example:    10.0 1 3 setncalvel 0.5 2 3 setncalvel (cal velocities of axis 3)
```

This instruction defines the calibration velocities for the cal instruction for individual axes.
Index=1 sets the speed towards the lower limit switch E0. Index=2 sets the speed taken during retraction from lower limit switch E0.

The unit is per default **rev/s**, for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.15. getrmvel

```
Syntax:     getrmvel
Parameter:  none
Response:   value1<CR><LF> value2<CR><LF> floating point numbers
Example:    getrmvel (get rm velocity and rm retract velocity)
```

This instruction reads the current range measure speeds. Value1 is the speed towards the upper limit switch EE. Value2 is the speed used during retraction from upper limit switch EE. There is only one pair of values for all axes. The unit is per default **rev/s** but can be turned to mm/s by setting the virtual 0-axis unit to 9 or -1.

13.16. setrmvel

```
Syntax:     [value] [index] setrmvel
Parameter:  [value] floating point number (larger than 0 to 20 mm/s)
            [index] 1=towards, 2=out of switch
Response:   none
Example:    10 1 setrmvel 0.5 2 setrmvel
```

This instruction sets the required range measure speeds. Index=1 sets the speed towards the upper limit switch EE. Index=2 sets the speed used during retraction from upper limit switch EE. There is only one pair of values for all axes. The unit is per default **rev/s** but can be turned to mm/s by setting the virtual 0-axis unit to 9 or -1.

13.17. getnrmvel

```
Syntax:     [axis] getnrmvel
Parameter:  axis 1,2,3,4 or -1 for all axes
Response:   value1<CR><LF>value2<CR><LF> (2 floating point numbers per axis)
Example:    2 getnrmvel (get rm velocity and rm retract velocity of axis 2)
```

This instruction reads the current speeds used during range measure (rm). Value1 is the speed towards the upper limit switch EE. Value2 is the speed taken during retraction from upper limit switch EE.

The unit is per default **rev/s**, for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.18. setnrmvel

```
Syntax:     [value] [index] [axis] setnrmvel
Parameter:  [value] is the velocity as floating point number
            [index] is the parameter number: 1 (towards switch) or 2 (out of)
            [axis]  is 1,2,3,4
Response:   none
Example:    10 1 3 setnrmvel 0.5 2 3 setnrmvel (rm velocities of axis 3)
```

This instruction sets the required speeds used during range measure (rm).
Index=1 sets the speed towards the upper limit switch EE.
Index=2 is the speed taken during retraction from upper limit switch EE.

The unit is per default **rev/s**, for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.19. getrefvel

```
Syntax:     getrmvel
Parameter:  none
Response:   value<CR><LF> 0.010000<CR><LF> floating point numbers
Example:    getrmvel (get refmove fast velocity and refmove precise velocities)
```

This instruction reads the current range measure speeds. Value1 is a dummy value which returns the calvel1 that is used for finding the reference. The Value2 represents the here adjustable value for the precise velocity. The unit is per default **rev/s** and also depends on the virtual 0-axis pitch, but can be turned to mm/s by setting the virtual 0-axis unit to 9 (default) or -1.

13.20. setrefvel

```
Syntax:     [value] [index] setrmvel
Parameter:  [value] floating point number (larger than 0 to 20 mm/s)
Response:   none
Example:    5.0 2 setrefvel (set velocity to reference mark for axis 1 to 5)
```

Index=1 is a dummy value, as calvel1 is used to find the reference. Index=2 represents the here adjustable value for the precise reference search velocity. The unit is per default **rev/s** and also depends on the virtual 0-axis pitch, but can be turned to mm/s by setting the virtual 0-axis unit to 9 (default) or -1.

13.21. getnrefvel

```
Syntax:     [axis] getnrefvel
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   value1<CR><LF>value2<CR><LF> (2 floating point numbers per axis)
Example:    2 getnrefvel (get reference search velocities of axis 2)
```

This instruction reads the current reference mark speeds.
Value1 is the speed towards the reference mark. The TANGO takes calvel for it, so calvel 1 is returned here.
Value2 is the (slow) velocity for the final move to the mark, to precisely detect its position.

The unit is per default **rev/s** and also depends on the virtual 0-axis pitch for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.22. setnrefvel

```
Syntax:     [value] [index] [axis] setnrefvel
Parameter:  [value] is the velocity as floating point number
            [index] is the parameter number: (1=fast search), 2 = precise
            [axis]  is 1,2,3,4
Response:   none
Example:    4.0 2 3 setnrefvel (reference search velocity of axis 3 is set to 4.0)
```

This instruction defines the required reference mark velocities.
Index=1 sets the speed towards the reference mark.
TANGO: Index 1 is a dummy value, the search speed is taken from calvel.
Index=2 sets the (slow) velocity for the final move to the mark, to precisely detect its position.

The unit is per default **rev/s** and also depends on the virtual 0-axis pitch for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

13.23. getcaldone

```
Syntax:     [axis] getcaldone
Parameter:  axis 1,2,3,4 or -1 for all axes
Response:   cal and rm state of one or all axes as decimal number(s)
Example:    1 getcaldone  (query cal and rm executed state of axis 1)
            => 3           returns e.g. a 3 axis 1 = cal+rm already executed
            -1 getcaldone (query cal and rm executed state of all axes)
            => 3 3 1       returns 3 for axis 1 and 2 = cal+rm done, 1 for axis3
```

This instruction reads if a cal or rm instruction was executed on the specified axis.
Return value:

1	= no cal or rm executed yet on the axis
2	= cal executed (origin set) but no rm yet
3	= rm executed but no cal (more or less useless, would only define upper range limit)
4	= cal and rm executed on the axis

13.24. setpos (sp)

```
Syntax:     [value1] [value2*] [value3*] setpos
        or  [value1] [value2*] [value3*] sp
Parameter:  [valueN] desired position values* for the axes (depends on getdim)
Response:   none
Example:    0 0 0 setpos (assuming getdim = 3) set the positions here to 0
```

Used to set the current positions to zero. Else, see description below.
The number of arguments depends on ***getdim*** and the unit depends on ***getunit*** of the individual axes.

***Remarks:** In the Venus instruction set, setpos does not set the current axis positions to the here specified value. It shifts the existing zero position (which was e.g. defined by cal) by the here entered distance value. Only for position values 0, the position origin (0) is set at the current axis positions.
Therefore, **it is recommended to only set zero positions and not any other position values.**

```
Example:    10 10 10 setpos
shifts the axis origins by +10, resulting in pos = -10 at the former origin (0)
and all positions therefore are now shifted by -10. Or when the axis was at 35,
then it now is at 25.
```

By setting extmode = 1 in the TANGO instruction set, the behavior can be changed:
Then setpos sets the actual positions to the specified values.

```
Example:    10 10 10 setpos
Sets the current axis positions to 10.
```

13.25. setnpos (snp)

```
Syntax:     [value] [axis] setnpos
        or  [value] [axis] snp
Parameter:  [value] desired position value* for this axis (in unit of the axis)
            [axis] 1,2,3,4
Response:   none
Example:    0 1 setnpos
```

Used to set the current axis position to zero. Else, see description below.
The unit depends on ***getunit*** of the axis.

***Remarks:** In the Venus instruction set, setnpos does not set the current axis positions to the here specified value. It shifts the existing zero position (which was e.g. defined by ncal) by the here entered distance value. Only for position value 0, the position origin (0) is set at the current axis position.
Therefore, **it is recommended to only set zero positions and not any other position values.**

```
Example:    10 1 setnpos
shifts the axis origin by +10, resulting in npos = -10 at the former origin (0)
and all positions therefore are now shifted by -10. Or when the axis was at 35,
then it now is at 25.
```

By setting extmode = 1 in the TANGO instruction set, the behavior can be changed:
Then setnpos sets the actual positions to the specified values.

```
Example:    10 1 setpos
Sets the current axis position to 10.
```

14. Move Instructions

All move instructions include an automatic linear interpolation. Axes which are started together are reaching the destination at the same time (vector). Axes can also be started independently from each other. In this case each axis travel with their own parameters and may not reach their target positions at the same time.
Blocking instructions are available to generate an automatic position reached reply or execute multiple consecutive moves.

14.1. move (m)

```
Syntax:     [position1] [position*] [position*] move (m)
Parameter:  [positionN] target positions (*number depends on getdim)
Response:   none
Example:    1.23 4.56 7.89 m  (dim=3: 3 axis absolute move to 1.23,4.56,7.89)
            1.23 4.56 m       (dim=2: 2 axis absolute move to 1.23,4.56,7.89)
            10 10 m ge        (use blocking instruction for completion reply)
            10 10 m 0 0 r st  (use blocking instruction for completion reply)
            1 1 m 0 0 r 5 1 m (use blocking instruction for consecutive moves)
```

This instruction moves the available axes to the specified absolute position.
The number of required arguments depends on ***getdim***.
The unit depends on the value of ***getunit***.

14.2. nmove (nm)

```
Syntax:     [value] [axis] nmove (nm)
            [value] [mask] nmove (nm)
Parameter:  target positon of axis or axes
Response:   none
Example:    Single axis
            0.1 2 nm (absolute move axis 2 to 0.1 mm)
            100 3 nm (absolute move axis 3 to 100 mm)
            Bitmask Synchron move
            100 -5 nm (absolute move axis 1 and 3 to 100 mm)
            0.2 -3 nm (absolute move axis 1 and 2 to 0.2 mm)
```

This instruction moves the selected axis or axes to the specified absolute position in [mm].
Positive axis values move a single axis: 1,2,3,4
Combined negative values may be used to move multiple axes: -1, -2, -4, -8,
e.g. -3 moves axis 1 and 2, -6 moves axes 2 and 3 to the one specified position.

14.3. rmove (r)

```
Syntax:     [distance1] [distance2] [distance3] rmove (r)
Parameter:  delta position
Response:   none
Example:    0.1 0.2 0.3 rmove (move relative for 3 axes controller: getdim=3)
            10 0 r            (move relative for 2 axes controller: getdim=2)
            0 0 0 r           (blocking instruction: wait for all 3 axes
                               before next instruction is executed)
```

This instruction moves one or more axes relative to their actual position.
The number of arguments depends on ***getdim***.
The unit of the input numbers depends on the current value of ***getunit***.

If called with distance 0, it blocks the instruction interpreter as long as the axes are travelling.

14.4. nrmove (nr)

```
Syntax:     [value] [axis] nrmove (nr)
            [value] [mask] nrmove (nr)
Parameter:  delta positon of axis
Response:   none
Example:    Single axis
            0.1 2 nrmove (relative move axis 2 by +0.1 mm)
            -10 2 nrmove (relative move axis 2 by -10 mm)
            Bitmask Synchron move
            100 -5 nrmove (relative move axis 1 and 3 by +100 mm)
            0.2 -3 nrmove (relative move axis 1 and 2 by +0.2 mm)
```

This instruction moves the selected axis or axes relative to their actual position in [mm].
It blocks the instruction interpreter when an addressed axis is still travelling.
Positive axis values move a single axis: 1,2,3,4
Combined negative values may be used to move multiple axes: -1, -2, -4, -8,
e.g. -3 moves axis 1 and 2, -6 moves axes 2 and 3

14.5. speed

```
Syntax:     [speed] [axis] speed
Parameter:  [speed] velocity (default in rev/s, depends on virtual 0-axis)
            [axis]  1,2,3,4
Response:   none
Example:    0.5 1 speed  (X axis travels forward at 0.5)
            -10 2 speed  (Y axis travels backward at 10)
              0 1 speed  (stop speed travel of X axis)
            stopspeed    (stop speed travel of all axes at the default accel)
```

This instruction starts a per axis speed move, which travels at the desired speed until stopped.
Speed may be overwritten as desired and will change to the new value with the axis acceleration.
It can be ended by the ***stopspeed*** or ***abort*** instruction or individually by setting the axis speed to zero.

The unit is per default **rev/s**, for backward compatibility reasons of the Corvus controller.
This can be changed by either setting the unit of the virtual 0-axis to 9 or 10, which results in mm/s and then is also compatible with the Venus-2 instructions. Or by setting it to -1, which takes the unit from the individual axis unit setting. Please refer to the ***getunit*** and ***setunit*** description.

14.6. stopspeed

```
Syntax:     stopspeed
Parameter:  none
Response:   none
Example:    stopspeed
```

This instruction ends the speed move off all axes. The stop is executed at the axis acceleration (getnaccel).

14.7. randmove

```
Syntax:     randmove
Parameter:  none
Response:   none
Example:    randmove (starts random move on all active axes)
```

Randmove starts an endless random move on all active axes.
The position range for random moves can be set by the ***setlimit*** instruction or by performing a ***cal*** / ***rm*** move.
The velocity varies randomly from 50% to 100% of the selected axis velocity.

14.8. nrandmove

```
Syntax:     nrandmove
Parameter:  axis 1,2,3,4 or -1 for all axes
Response:   none
Example:    1 nrandmove (starts random move on axis 1 (X))
```

14.9. pos (p)

```
Syntax:     pos or p
Parameter:  none
Response:   Axis positions (depends on state of getunit, getdim, and getselpos)
```

This instruction reads the current axis positions. The number of values depends on the ***getdim*** instruction. The unit depends on the ***getunit*** instruction. The response is either the motor or the encoder position. Please refer ***getselpos*** and ***setselpos*** how to select the position source. ***Setpos*** can be used to set the current positions to a different value.

14.10. npos (np)

```
Syntax:     [axis] npos or np
Parameter:  axis 1,2,3 or 4
Response:   Axis position (depends on getselpos)
```

This instruction reads the current position of the specified axis. The unit depends on the ***getunit*** instruction. The response is either the motor or the encoder position. Please refer ***getselpos*** and ***setselpos*** how to select the position source. ***Setpos*** or ***setnpos*** can be used to set the current positions to a different value.

15. Joystick, Trackball and Handwheel Instructions

The so called HDI interface detects all manual input devices automatically. You are allowed to unplug, plug and exchange these input devices in a safe manner, e.g. the axes keep their position. So called "hot plug" is also provided: You need not to switch off the controller while changing the input devices.

15.1. getjoystick (gj)

```
Syntax:     getjoystick (gj)
Parameter:  none
Response:   0=disable, 1=enable
Example:    gj => 1 (joystick is enabled)
```

This instruction reads the manual joystick operation for all axes.

15.2. joystick (j)

```
Syntax:     [parameter] joystick (j)
Parameter:  [0,1] 0=disable, 1=enable
Response:   none
Example:    1 j (enable joystick operation)
```

This instruction enables or disables the manual joystick operation for all axes.

15.3. getnjoystick (gnj)

```
Syntax:     [axis] getnjoystick (gnj)
Parameter:  axis
Response:   0=disable, 1=enable
Example:    3 gnj => 1 (joystick of axis 3 is enabled)
```

This instruction reads the manual joystick operation.

15.4. njoystick (nj)

```
Syntax:     [parameter] [axis] njoystick (nj)
Parameter:  [0,1] 0=disable, 1=enable
Response:   none
Example:    0 2 nj (disable joystick operation for axis 2)
```

This instruction enables or disables the manual joystick operation for the specified axis.

15.5. getjoyassign

```
Syntax:     [axis] getjoyassign
Parameter:  axis
Response:   0,1,2,3,-1,-2,-3
Example:    2 getjoyassign => -2 (joystick direction of axis 2 is inverse)
```

This instruction reads the manual joystick axis directions.

15.6. setjoyassign

```
Syntax:     [parameter] [axis] setjoyassign
Parameter:  0 = joystick axis disabled
            1 = joystick axis assigned to axis 1, default direction
           -1 = joystick axis assigned to axis 1, inverse direction
            2 = joystick axis assigned to axis 2, default direction
           -2 = joystick axis assigned to axis 2, inverse direction
            3 = joystick axis assigned to axis 3, default direction
           -3 = joystick axis assigned to axis 3, inverse direction
Response:   none
Example:    0 3 setjoyassign (disable joystick operation for axis 3)
           -2 2 setjoyassign (inverse joystick direction for axis 2)
            1 1 setjoyassign (default joystick direction for axis 1)
            2 1 setjoyassign (not supported: assigning joy axis 2 to axis 1)
```

This instruction sets the direction and enables or disables joystick axes. Assigning joystick axes to a different controller axis is currently not supported.

15.7. getjoyspeed

```
Syntax:     getjoyspeed
Parameter:  none
Response:   actual maximum manual speed
Example:    getjoyspeed (returns maximum manual speed)
```

This instruction reads the actual maximum manual speed. The unit depends on the unit 0 (virtual axis).

15.8. setjoyspeed (js)

```
Syntax:     [parameter] setjoyspeed (js)
Parameter:  maximum manual speed (unit as specified with 0 setunit)
Response:   none
Example:    20 js (set maximum manual speed to 20mm/s, if 0 getunit is 2)
```

This instruction determines the maximum manual speed. This instruction affects all axes.
The unit depends on the unit 0 (virtual axis).

15.9. getjoybspeed

```
Syntax:     getjoybspeed
Parameter:  none
Response:   actual maximum manual speed if button is pressed
Example:    getjoyspeed (returns manual speed, unit as specified)
```

This instruction reads the actual maximum manual speed when the joystick button is pressed.
The unit depends on the unit 0 (virtual axis).

15.10. setjoybspeed

```
Syntax:     [parameter] setjoybspeed
Parameter:  maximum manual speed (unit as specified with 0 setunit)
Response:   none
Example:    2 setjoybspeed (set manual speed to 2mm/s, if 0 getunit is 2)
```

This instruction determines the maximum manual speed when the joystick button is pressed.
The unit depends on the unit 0 (virtual axis).

15.11. getnjoyspeed

```
Syntax:     [axis] getnjoyspeed
Parameter:  axis
Response:   actual maximum manual speed of requested axis
Example:    1 getnjoyspeed (responds maximum manual speed of axis 1)
```

This instruction reads the actual maximum manual speed of a single axis.
The unit depends on the unit 0 (virtual axis).

15.12. setnjoyspeed (njs)

```
Syntax:     [parameter] [axis] setnjoyspeed (njs)
Parameter:  maximum manual speed of requested axis in mm/s
Response:   none
Example:    20 2 njs (set maximum manual speed of axis 2 to 20mm/s)
```

This instruction determines the maximum manual speed of a single axis.
The unit depends on the unit 0 (virtual axis).

15.13. getmanaccel

```
Syntax:     getmanaccel
Parameter:  none
Response:   floating point number
Remarks:    The TANGO controller does not support an individual acceleration
            for the human input devices (e.g. joystick), setaccel value used.
```

15.14. setmanaccel

```
Syntax:     [value] setmanaccel
Parameter:  value is acceleration (as a floating point number)
Response:   none
Example:    The TANGO controller does not support an individual acceleration
            for the human input devices (e.g. joystick), setaccel value used.
```

15.15. getjoysticktype

Whenever a HDI device is connected to the controller, it is automatically detected by the TANGO.
This instruction is implemented for compatibility purpose only.

15.16. setjoysticktype

Whenever a HDI device is connected to the controller, it is automatically detected by the TANGO.
This instruction is implemented for compatibility purpose only.

15.17. getkey

```
Syntax:     getkey
Parameter:  none
Response:   [F1] [F2] [F3] [F4] (0=not pressed or 1 = pressed)
Example:    response 1 0 0 1 indicates F1 and F4 were pressed since last query.
```

This instruction reads, if one or more of the buttons on the joystick panel were pressed since the last getkey instruction. The keys are named F1 to F4.

15.18. getwheelratio

```
Syntax:     [axis] getwheelratio
Parameter:  axis 1,2,3,4
Response:   travel distance per handwheel knob revolution in [mm]
Example:    2 getwheelratio (returns distance per rev. of Y axis)
```

This instruction reads the handwheel travel distance per knob revolution. Also refer to getwheelbratio, which reads the alternate travel distance which can be selected by a button on the device.

15.19. setwheelratio

```
Syntax:     [distance] [axis] setwheelratio
Parameter:  axis 1,2,3,4 and distance in mm
Response:   none
Example:    1 14.4 setwheelratio (set X travel distance to 14.4mm/revolution)
```

This instruction sets, the handwheel travel distance per knob revolution. Also refer to setwheelbratio, which sets the alternate travel distance which can be selected by a button on the device.
The maximum speed of traveling can be limited by the “js” or “njs” instruction.

15.20. getwheelbratio

```
Syntax:     [axis] getwheelbratio
Parameter:  axis 1,2,3,4
Response:   travel distance per handwheel knob revolution in [mm]
Example:    1 getwheelbratio (returns distance per rev. of X axis)
```

This instruction reads the handwheel travel distance per knob revolution. Also refer to getwheelratio, which reads the alternate travel distance which can be selected by a button on the device.

15.21. setwheelbratio

```
Syntax:     [axis] [axis] setwheelbratio
Parameter:  axis 1,2,3,4 and distance in mm
Response:   none
Example:    1 1.4 setwheelbratio (set travel distance to 1.4mm/revolution)
```

This instruction sets, the handwheel travel distance per knob revolution. Also refer to setwheelratio, which sets the alternate travel distance which can be selected by a button on the device.
The maximum speed of traveling can be limited by the “js” or “njs” instruction.

16. Digital and Analogue I/O

The TANGO provides several digital I/O, two analogue outputs (channel 0 and 1) and one analogue input. These are available on the optional auxiliary I/O port.
The analogue output channel 2 is reserved for special purpose. Furthermore, the HDI Interface analogue inputs may be read as well, if no HDI-device is connected.

16.1. setdac

```
Syntax:      [parameter] [channel-ID] setdac
Parameter:   [0..100] analogue output in [%] 100% = 10 Volt
Channel-ID:  [0..2] channel number
Response:    none
Example:     53.2 1 setdac (set channel 1 to 53.2% = 5.32 Volt
```

Channel No	Connector	Pin	Signal Name
0	AUX-IO	10	ANOUT0
1	AUX-IO	11	ANOUT1
2	reserved	-	-

This instruction sets the values for analogue outputs in percent. Fractional numbers may be used, too.

16.2. getaout

```
Syntax:      [channel-ID] getaout
Channel-ID:  [1 or 2] channel number
Response:    [0..10000] analogue output voltage in [mV]
Example:     1 getaout (returns analog output voltage of channel 1 in mV)
```

Channel No	Connector	Pin	Signal Name
1	AUX-IO	10	ANOUT0
2	AUX-IO	11	ANOUT1

This instruction reads back the values of analogue outputs in millivolts.

16.3. setaout

```
Syntax:      [parameter] [channel-ID] setaout
Parameter:   [0..10000] analogue output voltage in [mV]
Channel-ID:  [1 or 2]   channel number
Response:    none
Example:     7500 1 setaout (set channel 1 to 7.5V)
```

Channel No	Connector	Pin	Signal Name
1	AUX-IO	10	ANOUT0
2	AUX-IO	11	ANOUT1

This instruction sets the analogue output voltages in millivolts.

16.4. getnout

```
Syntax:     [axis] getnout
Response:   [integer number 0...15] digital signal level bitmask
Example:    1 getnout (returns an integer value representing the output state)
```

Bitmask Number	Output Name
1	OUT 0
2	OUT 1
4	OUT 2
8	OUT 3

This instruction reads the current output state of the TANGO I/O1 or Multi I/O extension connector.
The axis parameter must be specified but is not supported (dummy).
Only available with TANGO PCI-E based controllers and TANGO 3 mini.

16.5. setnout

```
Syntax:     [bitmask] [axis] setnout
Parameter:  [integer number 0...15] digital signal level bitmask
Response:   none
Example:    10 1 setnout (set OUT1 and OUT3 to +24V)
```

Bitmask Number	Output Name
1	OUT 0
2	OUT 1
4	OUT 2
8	OUT 3

This instruction sets the output state of the TANGO I/O1 or Multi I/O extension connector.
The axis parameter must be specified but is not supported (dummy).
Only available with TANGO PCI-E based controllers and TANGO 3 mini.

17. Encoder and Closed Loop Instructions

The closed loop functionality requires encoder signals as precondition. These signals are automatically validated during each calibration. In case of valid encoder signals the user may use them as feedback for so called closed loop. If the closed loop mode is enabled, the system will use the encoder position as reference. If closed loop mode is disabled, the system will use calculated micro step position as reference.

17.1. getclperiod

```
Syntax:     [axis] getclperiod
Parameter:  axis
Response:   encoder period in ±[mm]
Example:    3 getclperiod =>  0.020000 (axis 3 has 20 µm encoder period)
            2 getclperiod => -0.500000 (axis 2 has 500µm and reversed direction)
```

This instruction reads the actual encoder period of the requested axis in mm.
If the encoder counting direction is reversed, the encoder period is negative.

17.2. setclperiod

```
Syntax:     [parameter] [axis] setclperiod
Parameter:  [±0..1] encoder period in [mm]
Response:   none
Example:    0.5 2 setclperiod (set axis 2 encoder period to 0.5 mm)
           -0.5 2 setclperiod (set with reversed counting direction)
```

This instruction defines the actual encoder period for the requested axis in mm.
A negative value reverses the counting direction.

17.3. getcloop

```
Syntax:     [axis] getcloop
Parameter:  [axis] 1,2,3,4 or -1 for all
Response:   status of closed loop (0=OFF and 1=ON)
Example:    1 getcloop => 1 (indicates closed loop is enabled for axis 1)
```

This instruction reads the actual closed loop state of the requested axis.
A return value of 1 means the closed loop is enabled, but does not indicate an active closed loop:
Closed loop is activated by either a ***cal*** instruction or after reset/power up, depending on ***setpowerup***.

17.4. setcloop

```
Syntax:     [parameter] [axis] setcloop
Parameter:  [parameter] 0 = disable or 1 = enable the closed loop
            [axis]      1,2,3,4
Response:   none
Example:    1 2 setcloop (enable closed loop for axis 2)
```

This instruction enables or disables the closed loop mode for the requested axis.
Closed loop is then activated by either a ***cal*** instruction or after reset/power up, depending on ***setpowerup***.

17.5. getclfactor

```
Syntax:     [axis] getclfactor
Parameter:  [axis] 1,2,3,4 or -1 for all
Response:   closed loop factor
Example:    2 getclfactor => 2000 (closed loop factor is 2000 for axis 2)
```

TANGO: This instruction reads the closed loop factor of the requested axis.

17.6. setclfactor

```
Syntax:     [parameter] [axis] setclfactor
Parameter:  [parameter] 0.. 25000 closed loop factor (indep. from resolution)
            [axis]      1,2,3,4
Response:   none
Example:    150 2 setclfactor (set closed loop factor 150 for axis 2)
```

TANGO: This instruction defines the required closed loop factor for the requested axis.

17.7. getselpos

```
Syntax:     [axis] getselpos
Parameter:  axis 1,2,3,4 or -1 for all axes
Response:   position source
Example:    1 getselpos => 1 (axis 1 positions are measured encoder positions)
```

This instruction reads, if the ***pos (p)*** instruction returns the encoder position (1) or the motor position (0).

17.8. getnselpos

Same as ***getselpos***.

17.9. setselpos

```
Syntax:     [parameter] [axis] setselpos
Parameter:  [0,1] encoder position reading is 0=disabled 1=enabled
            [axis] 1,2,3,4
Response:   none
Example:    1 2 setselpos (enable axis 2 encoder position reading)
```

This instruction defines if the ***pos (p)*** instruction returns the encoder position (1) or the motor position (0).

17.10. setnselpos

Same functionality as ***setselpos***.

17.11. getencamp

```
Syntax:     [axis] getencamp
Parameter:  axis
            -1 reads the amplitude of all axes (parameters depend on dim)
             1,2,3 reads the amplitude of axis 1(X) or 2(Y) or 3(Z)
Response:   encoder signal amplitude in percent
Example:    3 getencamp => 63 (axis 3 encoder amplitude at 63%)
           -1 getencamp => 79 81 63 (all encoder amplitudes when getdim=3)
```

Reads the actual encoder signal amplitude of the specified axis.

17.12. getenc

```
Syntax:     [axis] getenc
Parameter:  axis
Response:   status of encoder (0=OFF and 1=ON)
Example:    2 getenc => 1 (indicates encoder is enabled for axis 2)
```

This instruction reads the actual encoder state of the requested axis.
Enabling the encoder manually makes it possible to access the measuring system position by ***1 setselpos / pos*** without entering the closed loop.

17.13. setenc

```
Syntax:     [parameter] [axis] setenc
Parameter:  [0,1] 0 = disable or 1 = enable the encoder
Response:   none
Example:    1 2 setenc (enable encoder for axis 2)
```

This instruction enables or disables the encoder for the requested axis.
Disabling the encoder also disables the closed loop, if active.
Enabling the encoder manually makes it possible to access the measuring system position by ***1 setselpos / pos*** without entering the closed loop.

17.14. getscaleinterface

```
Syntax:     [axis] getscaleinterface
Parameter:  axis 1,2,3
Response:   0 : No encoder interface present
            1 : Quadrature encoder interface (RS422 A/B-TTL)
            2 : 5Vpp MR Analog sin/cos interface **
            3 : 1Vpp    Analog sin/cos interface **
Example:    2 getscaleinterface (read interface type of axis 2)
```

This instruction reads the encoder interface type of the specified axis.
** Older TANGO hardware might only provide a hard-wired 1Vpp or 5Vpp interface.
** Type 3 is supported from Firmware Version 1.60B and higher.

17.15. setscaleinterface

```
Syntax:     [type] [axis] setscaleinterface
Parameter:  axis 1,2,3
            type 1 : Quadrature encoder interface (RS422 A/B-TTL)
                 2 : 5Vpp MR Analog sin/cos interface **
                 3 : 1Vpp    Analog sin/cos interface **
Response:   none
Example:    1 3 setscaleinterface (interface of axis 3 is Quadrature RS422/TTL)
```

This instruction sets the encoder interface type of the specified axis.
** Analogue 1Vpp or 5Vpp interpolation capabilities must be configured either by order or activation code.
** Older TANGO hardware (Desktop, PCI, PCI-S, PCI-E) might only support either 1Vpp or 5Vpp MR.

17.16. getclwindow

```
Syntax:     [axis] getclwindow
Parameter:  [axis] 1,2,3,4 or -1 for all axes
Response:   [window] in the unit of the axis
Example:    2 getclwindow   => 0.001000
           -1 getclwindow   => 0.001000 0.001000 0.001000 (if getdim=3)
```

This instruction reads the closed loop target window of the specified axis.
The window unit depends on getunit of the corresponding axis.

17.17. setclwindow

```
Syntax:     [window] [axis] setclwindow
Or          [window in mm] 0 [status] [signal] [axis] setclwindow (compatible)
Parameter:  window = closed loop position window 0.0001 .. 1.0mm in the axis unit
            status = 0: status, nstatus info bit D5 disabled
                   = 1: status, nstatus info bit D5 enabled
            signal    : dummy value
Response:   none
Example:    0.0001 2 setclwindow      (set the window to ±100nm, when unit=mm)
Or          0.0001 0 1 0 2 setclwindow
           (axis 2 has a 100nm window, D5 status output of "in window" state)
            0.0020 0 0 0 2 setclwindow
           (axis 2 has a 2µm window, no D5 status output)
```

This instruction defines the closed loop position window and status settings for the requested axis.
The instruction also accepts the larger syntax but only uses the `[window in mm]` and `[axis]` parameters.
The window unit depends on getunit of the corresponding axis.

17.18. getclwintime

```
Syntax:     [axis] getclwintime
Parameter:  [axis] 1,2,3,4
Response:   [time in seconds]
Example:    1 getclwintime
Reply:      0.100
```

This instruction reads how long the closed loop position must be in the target window.

17.19. setclwintime

```
Syntax:     [time in seconds] [axis] setclwintime
Parameter:  axis, time [0 … 1.000 s]
Response:   none
Example:    0.05 1 setclwintime
           (closed loop of axis 1 must remain in the position window for 50 ms)
```

This instruction defines how long the closed loop position must be in the target window in [ms].

18. Trigger Instructions

The TANGO controller can generate either position dependent or periodic signals to trigger external components, e.g. cameras, illumination, laser etc. The trigger function can be assigned to one axis only. TANGO Desktop, PCI-S and PCI-E and TANGO 3 mini controllers can generate up to two trigger signals. The second trigger output may be used to generate a precise delay (refer to settrout instruction).
When using encoder signals as trigger position source, please make sure that the encoders are enabled and activated by the TANGO before executing settrpara. Usually encoders are activated after executing the calibrate instruction.

The trigger instructions are:

- ***settr*** sets the trigger mode (to disabled, enabled as position dependent or periodic)
- ***settrout*** selects the trigger output(s) 1, 2 or 1+2
- ***settrpol*** selects the output signal polarity (active high or low)
- ***settrlen*** set the output signal length (pulse width)
- ***settrcount*** a counter that counts the generated trigger pulses, read by *gettrcount*
- ***settrselpos*** selects the position source (motor position or encoder position)
- ***settrdelay*** optional time delay for 2nd trigger output compared to 1st output
- ***settrf*** set the free running trigger frequency in trigger mode 2 (refer to *settr*)
- ***settrpara*** sets and enables the position dependent trigger (positions, number of pulses)

Trigger example:

```
0 1 settr               disable the trigger (here: for axis 1/X)
0 2 settr               disable the trigger (here: for axis 2/Y)
0 3 settr               disable the trigger (here: for axis 3/Z)
1 settrout              select trigger output    (e.g. here: output 1)
1 settrpol              set trigger polarity     (e.g. here: active high)
0.04 settrlen           set trigger pulse width  (e.g. here: 40µs)
1 settrselpos           set trigger source       (e.g. here: encoder)
                        --> initialization is complete, now move and trigger
9 20 5 m                move to start position   (slightly before 1st trigger)
1 1 settr               assign trigger to axis   (here: X axis)
10 20 11 1 settrpara    set and enable X trigger (here: 11x - at 10,11, ...20)
0 settrcount            option in case the generated triggers should be checked
21 20 5 m               move to end position     (slightly past final trigger)
gettrcount              ==> 11                   (optional counter read)
...
```

Remarks:

1) It is good practice to use ge (read back the get error instruction) after each set instruction in order to detect errors and to avoid receive buffer overflow.

2) The end of a move can be checked in different ways, this example doesn't take care of it.

18.1. gettr

```
Syntax:     [axis] gettr
Parameter:  axis
Response:   trigger mode for specified axis
            0 = Trigger disabled
            1 = Scan-Trigger (positions)
            2 = Free running trigger (periodic signal)
Example:    1 gettr => 0 (trigger for axis 1 is disabled)
```

This instruction reads the trigger mode of the specified axis. Only one axis can be active at a time.

18.2. settr

```
Syntax:     [trigger mode] [axis] settr
Parameter:  trigger mode: 0 = Trigger disabled
                          1 = Scan-Trigger (positions)
                          2 = Free running trigger (periodic signal)
            axis
Response:   none
Example:    2 1 settr (set trigger mode to permanent frequency output)
```

This instruction sets the trigger mode for the specified axis. Only one axis can be active at a time.

18.3. gettrout

```
Syntax:     gettrout
Parameter:  none
Response:   trigger output mode
Example:    1 gettrout => 11
            (both trigger outputs are used, output 2 is in precise delay mode)
            1 gettrout => 1
            (default trigger output mode on most TANGO controllers)
```

This instruction reads the trigger output mode. For a table of trigger modes, please refer to ***settrout***.

18.4. settrout

```
Syntax:     [trigger output mode] settrout
Parameter:  trigger output modes:
            AUX-I/O Output |STANDARD|PREC.WIDTH2|PREC.DELAY2|PREC.FREQUENCY2|
            ---------------+--------+-----------+-----------+---------------+
            [no]           |    0   |    (4)    |    (8)    |      (12)     |
            ---------------+--------+-----------+-----------+---------------+
            TRIGGER_OUT    |    1   |    (5)    |    (9)    |      (13)     |
            ---------------+--------+-----------+-----------+---------------+
            TAKT_OUT       |    2   |     6     |    10     |       14      |
            ---------------+--------+-----------+-----------+---------------+
            TRIGGER+TAKT   |    3   |     7     |   11 **   |       15      |
            ---------------+--------+-----------+-----------+---------------+
            ** required for precise delay of secondary trigger output
Response:   none
Example:    1 settrout (default mode for TANGO controllers)
            3 settrout (secondary trigger output does the same as main trigger)
           11 settrout (secondary trigger signal after trdelay time)
```

This instruction defines the trigger output mode. Modes 4..7 and 12..15 are currently not available.

18.5. gettrpol

```
Syntax:     gettrpol
Parameter:  none
Response:   trigger polarity
            0 = falling edge, active low
            1 = rising  edge, active high (default)
Example:    gettrpol => 1
```

This instruction reads the trigger output polarity.

18.6. settrpol

```
Syntax:     [polarity] settrpol
Parameter:  0 = falling edge, active low
            1 = rising  edge, active high (default)
Response:   none
Example:    1 settrpol (set trigger polarity to active high)
```

This instruction defines the trigger output polarity.

18.7. gettrlen

```
Syntax:     gettrlen
Parameter:  none
Response:   trigger pulse length in Milliseconds [ms]
            0.000 ~ 25000.000
Example:    gettrlen => 0.040 (trigger pulse length is 40µs)
```

This instruction reads the trigger output signal length.

18.8. settrlen

```
Syntax:     [trigger pulse length] settrlen
Parameter:  0.00 ~ 25000 (in 0.04 ms steps)
Response:   none
Example:    0.04 settrlen (set trigger pulse length to 40µs)
            10 settrlen (set trigger pulse length to 10ms)
            0 settrlen (set pulse to shortest possible length)
```

This instruction defines the trigger output signal length in milliseconds.

18.9. gettrcount

```
Syntax:     gettrcount
Parameter:  none
Response:   Number of generated trigger events
            (since trigger enabled or resetted)
Example:    gettrcount => 100 (100 trigger pulses have been generated)
```

This instruction reads the trigger event counter.

18.10. settrcount

```
Syntax:     [count] settrcount
Parameter:  new trigger counter value, typically 0
            0 ~ 2147483647
Response:   none
Example:    0 settrcount (reset trigger counter)
```

This instruction sets the trigger event counter to the specified count.

18.11. gettrselpos

```
Syntax:     gettrselpos
Parameter:  none
Response:   Trigger source:
            0 = Motor position
            1 = Encoder position
Example:    gettrselpos => 0 (trigger uses internal motor position)
```

This instruction reads the trigger position source.

18.12. settrselpos

```
Syntax:     [position source] settrselpos
Parameter:  Trigger source: 0 = Motor position
                            1 = Encoder position (only with analogue encoders)
Response:   none
Example:    1 settrselpos (trigger uses encoder position)
```

This instruction defines the trigger position source.

Remarks: When using encoder position (1), please ensure that the encoders are enabled and activated before executing settrpara. Else the TANGO will use the motor position even if trselpos is set to 1.
Usually encoders are activated after executing the calibrate instruction.
Encoder position dependent trigger is only available with analogue sin/cos encoders. In case of A/B TTL encoders, the trigger source 0 (motor position) must be used.

18.13. gettrdelay

```
Syntax:     [axis**] gettrdelay
Parameter:  axis
Response:   trigger signal delay for secondary trigger output in [µs]
Example:    1 gettrdelay => 1.5 (trigger delay is 1.5 µs)
```

This instruction reads the delay of the secondary trigger signal.
** The axis parameter must be used for compatibility but is ignored internally (one delay applies to all axes).

18.14. settrdelay

```
Syntax:     [delay] [axis**] settrdelay
Parameter:  [0.0 .. 32500000.0]
            trigger signal delay for secondary trigger output in [µs]
Response:   none
Example:    10.5 1 settrdelay (set trigger signal delay to 10.5 µs)
```

This instruction defines the delay of the secondary trigger signal, which is used when settrout option 11 is set.
This function is only available with TANGO PCI-E based controllers and TANGO 3 mini.
** The axis parameter must be used for compatibility but is ignored internally (same delay for all axes).

18.15. gettrf

```
Syntax:     [axis**] gettrf
Parameter:  axis
Response:   trigger frequency in [Hz]
Example:    1 gettrf => 10.000 (trigger frequency is 10 Hz)
```

This instruction reads the trigger frequency of periodic signal (for settr mode 2).
** The axis parameter must be used for compatibility but is ignored internally (one delay applies to all axes).

18.16. settrf

```
Syntax:     [frequency] [axis**] settrf
Parameter:  [0.010 .. 12500.000]
            trigger frequency in [Hz]
Response:   none
Example:    1000 1 settrf (set trigger frequency to 1kHz)
```

This instruction defines the trigger frequency of periodic signal (for settr mode 2).
** The axis parameter must be used for compatibility but is ignored internally (same delay for all axes).

18.17. gettrpara

```
Syntax:     [axis] gettrpara
Parameter:  axis
Response:   [startpos] [endpos] [count]
            trigger parameter for specified axis
Example:    1 gettrpara => 10.0000 90.0000 5
           (5 equidistant trigger points from 10 to 90 mm: 10, 30, 50, ...)
```

This instruction reads the trigger position settings (for settr mode 1).

18.18. settrpara

```
Syntax:     [startpos] [endpos] [count] [axis] settrpara
Parameter:  startpos = position where first trigger is generated
            endpos   = position where last trigger is generated
            count    = number of equidistant trigger points **
            axis     = which axis to be used
Response:   none
Example:    10 110 11 1 settrpara (11 trigger positions in X from 10 to 110 mm)

            110 10 11 1 settrpara (same, but in reverse direction)

            5.553 7.553 21 2 settrpara
            (21 trigger positions in Y, trigger distance is 0.1µm)

            100 100 1 1 settrpara (one trigger at 100 mm)
            (The trigger direction then depends on the axis position)
```

This instruction defines equidistant trigger positions from a start- to an endpoint (when in settr mode 1).
The trigger direction is unidirectional.
The axis position must be in front of the trigger start position in order to charge the trigger.
As long as the settr mode 1 is not changed, the trigger will recharge after returning to a position in front of the trigger start position.
Also, the last trigger will be generated when passing the last trigger position, meaning the move must go slightly farther than the last trigger position.
If only one trigger must be generated, the axis position at which the settrpara or settr instruction was executed determines the trigger direction (pos < triggerpos → positive, pos > triggerpos → negative).

Remarks:
In general, it is good practice to allow the axis to accelerate to its constant velocity before reaching the first trigger position and begin deceleration after the last trigger. This will deliver the best possible results, at least when triggering in open loop applications without a measuring system.

As the first trigger is released at the start position, please consider that e.g. triggering from position 10 to 20 requires 11 counts to achieve a 1mm trigger distance.

** The number of trigger points is limited. Depending on the firmware and controller type a maximum of 2047, 8191 or 10000 triggers is possible. If more than the available trigger positions are specified, settrpara will generate an error.

19. Wait Instructions

19.1. waittime (wt)

```
Syntax:     [time] [unit] wt
Parameter:  time,
            unit: 0 = ticks of 0.25ms    (time =     1 ... 65000 ticks = 16.25s)
                  1 = seconds            (time = 0.001 ...   240 s)
Response:   --
Example:    1 1 waittime (wait one second)
            2.5 1 wt     (wait 2.5 seconds)
            2 0 wt       (wait 0.5 milliseconds)
```

This instruction prevents execution of the following instructions for the specified time.
Two units are available: ticks (in 0.25ms) and seconds (resolution down to 1ms).

20. Safety Instructions

20.1. abort (a)

```
Syntax:     abort
            or a
            or Ctrl+C (0x03 hex)
Parameter:  none
Response:   none
Example:    a
```

This instruction stops all axes. May not work with blocking instructions.
In such case it is recommended to to send the abort character “Ctrl-C” (hex 0x03), which works independent of the instruction interpreter and also aborts blocking instructions.

20.2. nabort

```
Syntax:     [axis] nabort
Parameter:  axis 1,2,3 or 4
Response:   none
Example:    2 nabort
```

This instruction stops individual axes. May not work with blocking instructions.
In such case it is recommended to to send the abort character “Ctrl-C” (hex 0x03), which also aborts blocking instructions but stops all axes.

20.3. getinfunc

```
Syntax:     [input] [axis] getinfunc
Parameter:  input = Digital input to which the functionality is assigned
            axis  = Axis to which the functionality is assigned
Response:   current functionality of the selected input (refer to setinfunc)
Example:    1 3 getinfunc ==> 3 (digital input #1 of Z-axis has functionality 3)
```

This instruction reads the stop signal configuration.

20.4. setinfunc

```
Syntax:     [function] [input] [axis] setinfunc
            [function] 0 0 setinfunc ***
Parameter:  *** The TANGO AUX-I/O stop input is addressed by sending axis and
                input as 0 (zeros). It is always assigned to all axes.

            input    = Digital input to which the functionality is assigned
            axis     = Axis to which the functionality is assigned
            function =

            -1 = clears a latched (sticky) stop condition

             0 = Stop function disabled
             1 = not available
             2 = not available
             3 = not available

            20 = stoppol  0 active low  \ stopped as long as signal applied
            21 = stoppol  1 active high / joystick operation remains enabled

            22 = stoppol  2 active low  \ stopped as long as signal applied
            23 = stoppol  3 active high / joystick operation disabled

            24 = stoppol  4 active low  \ stop latched until "-1 0 0 setinfunc"
            25 = stoppol  5 active high / joystick operation disabled

            28 = like 20, waits until any active move has completed
            29 = like 21, waits until any active move has completed

            30 = like 22, waits until any active move has completed
            31 = like 23, waits until any active move has completed

            32 = like 24, waits until any active move has completed
            33 = like 25, waits until any active move has completed

Response:   --
Example:    0 5 2 setinfunc  (disable stop function of Y-axis digital input #5)
            21 0 0 setinfunc (TANGO: set the stop input to stoppol 1 mode)
            -1 0 0 setinfunc (TANGO: clear a latched stop condition)
```

This instruction configures the stop signal functionality of the specified digital input and axis.

20.5. getmp

```
Syntax:     [axis] getmp
Parameter:  axis  = 1,2,3,4 or -1 for all axes
Response:   motorpower state: 0=power is off, 1=power is on (default)
Example:    -1 getmp ==> 1 1 1
             2 getmp ==> 1
```

Get Motor Power. This instruction reads the on/off state of the motor power amplifier(s).

20.6. setmp

```
Syntax:     [value] [axis] setmp
Parameter:  axis  = 1,2,3 or 4
            value = 0 (switch motor power off), 1 (switch motor power on)
Response:   --
Example:    0 3 setmp (switch the motor power of axis 3 off)
```

Set Motor Power. This instruction sets the on/off state of the specified motor power amplifier.

21. Dummy Instructions

Dummy instructions are implemented for compatibility only. They do not affect the controller's behaviour.

21.1. getmotorpara

```
Syntax:     [index] [axis] getmotorpara
Parameter:  index 1,2 or 3
            axis  1,2,3 or 4
Response:   index=3: [I²t limit] [current I²t value] as integer
Example:    3 1 getmotorpara (returns X-axis values, e.g. 40000 92)
            2 1 getmotorpara (returns X-axis values, e.g. 0.000000 0)
```

21.2. setmotorpara

```
Syntax:     [value] 3 [axis] setmotorpara
Parameter:  maximum I²t value
            axis index 1,2,3 or 4
Response:   --
Example:    40000 3 1 setmotorpara (set X-axis I²t limit to 40000)
```

21.3. getclpara

```
Syntax:     [axis] getclpara
Parameter:  [axis] 1,2,3 or 4
Response:   [P] [I] [D] as floating point numbers
Example:    1 getclpara (returns 0 2 0.15)
```

21.4. setclpara

```
Syntax:     [P] [I] [D] [16383] [SP5] [SP6] [dpos] [ivel] [cutoff] [SP10] [np] [axis] setclpara
Parameter:  Closed loop parameter or subset of parameter defined by [np]
            np is 1 to 10, depending on the number of parameters sent
            [axis] 1,2,3 or 4
Response:   --
Example:    0 5.3 0.001 3 1 setclpara (only set PID parameters of X-axis)
```

21.5. getsp

```
Syntax:     [SP index] [axis] getsp
Parameter:  [SP index] SP Parameter index 1 to 10 as integer,
            [axis]     1,2,3 or 4
Response:   Specified parameter as float or integer, depending on parameter
Example:    2 1 getsp (returns closed loop parameter 2 = I param. for X-axis)
```

21.6. setsp

```
Syntax:     [value] [SP index] [axis] setsp
Parameter:  [value]    as float or integer, depending on indexed parameter
            [SP index] SP Parameter index 1 to 10 as integer,
            [axis]     1,2,3 or 4
Response:   --
Example:    0.15 3 2 setsp (set closed loop D parameter of Y-axis to 0.15)
```

Set the Parameters SP1 to SP10 of the Closed Loop. Availability of Parameters vary by controller type.

22. Table of Error Numbers

The response to instruction ***geterror (ge)*** is an error number. The following table contains a description of these error numbers and a description of the possible root cause.

Error Number	Description
0	no error
1001	wrong parameter type
1002	not enough parameters on the stack for the instruction
1003	invalid parameter
1004	move stopped working range should run over
1007	invalid parameter value
1008	stack is empty (or contains not enough parameters)
1009	stack is full
1015	parameter outside allowed limits
1020	arc tan
1027	
1029	
1100	division through zero
1200	non-volatile memory write error
1234	error during calibration
2000	unknown instruction

Please refer instruction ***geterror (ge)*** for further details.

23. Document Revision History

No.	Revision	Date	Changes	Remarks
01		17. June 2008		birthday
	A	23. February 2010	Description corrected: setcalvel, setrmvel, setncalvel, setnrmvel Added instructions: setrefvel, getrefvel, setnrefvel, getnrefvel	Firmware 1.51
	B	07. April 2010	Extended description of geterror	
	C	20. July 2010	New MW Logo	
	D	22. July 2010	Added instructions: getwheelratio, setwheelratio, getwheelbratio, setwheelbratio,	Firmware 1.521
	E	29. July 2010	Description of status (st) corrected, Added instructions nstatus (nst), setclwindow, getclwindow, setclwintime, getclwintime, getnaccelfunc, setnaccelfunc, nclear, getjoystick (gj), njoystick (nj), getnjoystick (gnj), getnerror (gne)	Firmware 1.522
	F	26. August 2010	Added instructions getaout, setaout, changed document title from “MST Dokument” to “TANGO Instruction Set Venus”	Firmware 1.528
	G	07. October 2010	Added trigger instructions: gettr,settr, gettrout,settrout, gettrselpos,settrselpos, gettrdelay,settrdelay, settrf,getttrf, gettrpara,settrpara	Firmware 1.534
	H	28. October 2010	setpowerup example corrected, getpowerup description nmove, nrmove with bitmask, extended powerup, randmove	Firmware 1.543
	I	01. December 2010	Added instructions: getjoyassign, setjoyassign, tango	Firmware 1.561
	J	10. February 2011	Improved description of trigger functionality	
	K	15. February 2011	gettrpol, settrpol, gettrlen, settrlen, gettrcount, settrcount	Firmware 1.5682
	L	17. February 2011	Added waittime (wt), improved description of move	Firmware 1.5691
		04. March 2011	Added speed, stopspeed, nabort, improved abort description	Firmware 1.56
	M	08. March 2011	Added setenc, getenc	Firmware 1.57
			Added getencamp	Firmware 1.57
		10. March 2011	Added getscaleinterface, setscaleinterface	Firmware 1.57
		12. August 2011	Added getnsecvel, setnsecvel, Added dummy instructions: getmotorpara, setmotorpara, getclpara, setclpara, getsp, setsp	Firmware 1.57
		01. Sept. 2011	Added getinfunc, setinfunc, getstageno getserialno now reports TANGO S/N	Firmware 1.57
		11. October 2011	Added getmotiondir, setmotiondir	Firmware 1.57
		14. December 2011	Added setnout, getnout	Firmware 1.57
		20. July 2012	Changed setnout, getnout description to I/O1	Firmware 1.57
		07. Sept. 2012	Naming conventions	Firmware 1.57
		26. October 2012	Improved settrpara description Added setncaltimeout, getncaltimeout Corrected description of setdim	Firmware 1.59
	N	18. February 2013	Document released for TANGO Firmware 1.60	Firmware 1.60
		22. October 2013	New functionality of getaxis instruction: Returns -1 if no axis Unified, consistent use of the term “instruction”	Firmware 1.62
		25. June 2015	Modified stack description	
		21. October 2015	Added instructions, improved descriptions, extended trigger descriptions and settrpara	Firmware 1.66
	O	10. November 2015	Improved command set explanation, introduction Document released for TANGO Firmware 1.66	Firmware 1.66
		04. July 2018	Added getcaldone instruction	Firmware 1.70

	P	01. August 2018	Release for TANGO Firmware versions 1.70 / 1.60S5	Firmware 1.70
		13. January 2020	Correced setlim parameter description first all lower limits, then all upper, not alternating lower/upper	Firmware 1.72B
	Q	24. February 2020	Document type changed from .odt to .docx	
		24. Sept. 2021	Added setkeeprm, getkeeprm instructions	Firmware 1.74
		28. Sept. 2021	Added setipadr/getipadr, setnetmask/getnetmask, setgateway/getgateway, getmacadr	Desktop HE, Firmware 1.74
		22. October 2021	Added setmp/getmp, re-formatted the document layout	
		22. November 2021	Added option for negative setclperiod/getclperiod values Added optional Venus-1 syntax for setclwindow	Firmware 1.74
	R	22. December 2021	Release for Firmware 1.74	Firmware 1.74
		01. April 2022	Revised explanations	
	S	24. July 2022	Release for Firmware 1.75, also applies to Firmware 1.74	
		29. Sept. 2022	Corrected setsecvel description to "always in mm/s"	
	T	21. December 2022	Added setnstopdecel, getnstopdecel, nrandmove, -1 and -2 setunit options, general revision of the document.	Firmware 1.76