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# Release Note

## MPI/XMP

### Firmware and Library

XMP Firmware Version 371A5

MPI Library Version 20020117.1.6.1.3


Revised 12Sep2008

DCR 798

## 1 Introduction

Welcome to the latest release of Motion Engineering's MPI/XMP Firmware and Motion Programming Interface Library. This distribution has been prepared for Windows® NT 4.0, Windows® 2000 and Windows® 95/98. The distribution was built using Visual C++ v4.2 and tested using Visual C++ v6.0. This document provides an overview of the release, and describes the new features, changes and bug fixes between the following versions:

	Previous Version	New Version
Firmware	371A5	371A5
MPI Library	20020117.1.6.1.2	20020117.1.6.1.3



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## The XMP-PULSE is now supported by the MPI Library

The XMP-PULSE-PCI motion controller is designed as a cost-effective, XMP-series motion controller specifically designed for pulse (step/direction) control drives having up to 32 axes. For a detailed explanation of its specifications and features, please see **Application Note 218, Rev. A**. For further information, please contact **Motion Engineering, Inc.**

## 1.1 System Requirements

### 1.1.1 Operating System

The MPI release is built to operate on Windows® NT 4.0, Windows® 2000 or Windows® 95/98.

### 1.1.2 Visual C++ DLLs

The MPI is built using Microsoft Visual C++ 4.2. No Microsoft Visual C++ DLLs are included with this release. These DLLs are required in order to run programs built with the MPI. These DLLs work with Microsoft Visual C++ 4.2 - 6.

## 1.2 Installing the Distribution



### **WARNING! You must reboot your system!**

If you have not used a InstallShield for Windows Installer program before, the MEI Install Shield will need to install InstallShield installer files before actually installing the MDK. You will have to **reboot** your system after these files are installed. Please shut down all programs before running the InstallShield for the first time. For first-time installations of an MEI controller and accompanying software, please see the *QuickStart Guide* located on the distribution CD.



**WARNING!** If you are upgrading from a previous MPI/XMP software release, **you will need to remove or archive all previous releases**. This will prevent any conflicts between old and new files. To remove the previous MPI/XMP software release, select **Start -> Control Panel -> Add/Remove Programs**. Select the **MPI/XMP Development Toolkit** entry and click on the **Add/Remove** button.

NOTE: The MPI/XMP software release can also be removed by running the MDK InstallShield and choosing the remove option.

For more information on installing the MPI/XMP software release, please see the *QuickStart Guide*.

The MPI/XMP distribution comes in two parts. The first part is an InstallShield distribution. Key components of the distribution are:

- device driver (meixmp.sys for WinNT, meixmp.vxd for Win95)
- firmware
- MPI dynamic link library
- utilities
- sample applications

To install the MPI/XMP software release, insert the MDK CD-ROM. The set-up InstallShield will be launched automatically. Follow the InstallShield instructions. The InstallShield will take care of installing the DLL and will also set the PATH environment variable to XMP\bin\WinNT for WinNT and Win2000, or XMP/bin/Windows for Win95/98 under the default installation directory (**C:\MEI**).

The second component of this distribution contains customer-specific applications and files. This is provided to you in a separate InstallShield. To install this custom component, click on the InstallShield (default C:\MEI) and follow the instructions.

By default, files will be located in the C:\MEI\Custom directory. To install into an alternate directory, select the custom option during the installation process and change the default directory to the one you prefer.

## 2 General Changes

This section lists changes since the 20000913 production release, beginning with the most recent.

### 2.1 Addition of Multiple Injection Point Noise Source to xmp firmware

**MPI 899**

In firmware version "371A5," a noise source input was added. This feature can be used to inject noise into the control loop of a specific axis to generate a bode plot of the physical system. This functionality can be accessed using MEI's bode tool software versions 01.02.01 and later.

**WARNING!** This tool should never be used during a system's normal operation - system instability may result.

### 2.2 Multi-Point Motion Buffering Improvements

**MPI 889**

Changes have been made to the 20020117.1.3 release to streamline the loading of points lists. Now, only the initial point list is loaded by the host. Now, Motion Modifies only append to the host's point list and does not initiate a load. The eventMgr service thread (as supplied by the service module of apputil) performs all subsequent point list loads upon internal "frame low" events. Frame low events are now generated every sample that the controller has less points than the frame low limit. These changes were implemented in version 20020117.1.4.

### 2.3 New On-Line Documentation System

MEI would like to introduce its new On-Line Documentation System. This html-based documentation system will dramatically improve your ability to navigate through the technical documentation and find the information that you need. The web site will be accessible and functional through the Internet (<http://support1.motioneng.com>) and through our Install Shield CD-ROM, which will allow any computer to use the web site without a network connection. There are several new features including: conditional pulldown menu bars, keyword search functionality, new sample applications, a PDF/Notes section, and dynamic hyperlinking throughout the site. To learn more about the features of this site and how you can best optimize your time and effort, simply click on the "How to use this Site" link which is on the home page and take a minute to read the page. This section will help you understand how the site is structured and how you can fully take advantage of this new documentation system.

### 2.4 New Default XMP-Series Controller Configuration

**MPI 667**

The XMP-Series controller's Flash memory is now pre-loaded at the factory with base firmware. This firmware contains a minimal amount of code to boot the DSP and allows the MPI to identify the XMP-Series controller. To operate the controller you will need to download the binary code included in this MPI software distribution. Please see the sections below for a complete description about software binary management and instructions to download firmware to your controller.

## **Introduction**

System designers need to give careful consideration to the software configuration management procedures for their machines. To ensure machine consistency and quality, a process for software installation, configuration, version control, and verification must be implemented. Addressing this issue early in the development cycle will significantly reduce confusion and mistakes. Failure to implement some basic procedures can cause unknown machine configurations, costly field repairs/upgrades, mysterious intermittent problems, broken equipment, and possible injury.

The MPI and XMP-Series controllers contain several features to make configuration management easy. Please take the time to understand and implement these features before you begin development.

## **Software Components**

The MEI software distribution contains several software components, which need to be loaded onto your machine and controller. The MPI DLL, header files, import libraries, device driver, utility programs, controller binaries, sample code, etc. These are all loaded onto your hard drive by the InstallShield distribution. Additionally, the controller contains on-board flash memory to store DSP code, FPGA code, and configuration information. You will also need to load the appropriate DSP (.bin) and FPGA (.fpg) code into your controller's flash memory. The code is loaded into the DSP and FPGA(s) during power-on or when the controller is reset.

## **Version Control**

Each software component has its own version number. These components have been tested together at the factory for interoperability.

The software version numbers have the following format:

Motion Console	NN.NN.nn	Major, Medium, minor
Motion Scope	NN.NN.nn	Major, Medium, minor
MPI DLL	YYYYMMDD.b...r	Year, Month, Day, branch, ... rev
XMP Firmware	NNNnn	Major, minor
FPGA Code	RRR	Revision

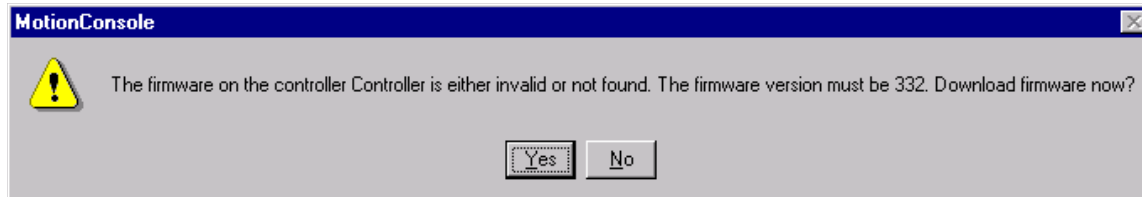
The software has automated compatibility checking. If there is a compatibility problem between software components an error code will be returned.

If an application (Motion Console and Motion Scope are applications too) and MPI DLL are NOT compatible, the error message "Control: application not compatible with MPI DLL" will be returned. To correct this problem, you can recompile your application with the appropriate MPI import library OR install the proper MPI DLL.

If the MPI DLL and firmware versions are NOT compatible, the error message "Control: firmware version mismatch" will be returned. The user or application must download the appropriate firmware to correct the problem. The DLL and firmware versions can be determined with the version.exe utility, Motion Console, or application code.

If the controller flash memory has NOT been configured, the error message "Control: no firmware found (factory default)" will be returned. To correct this problem, the user or application must download the appropriate XMP firmware and FPGA images. Firmware and FPGA images can be downloaded from Motion Console, flash.exe, or application code.

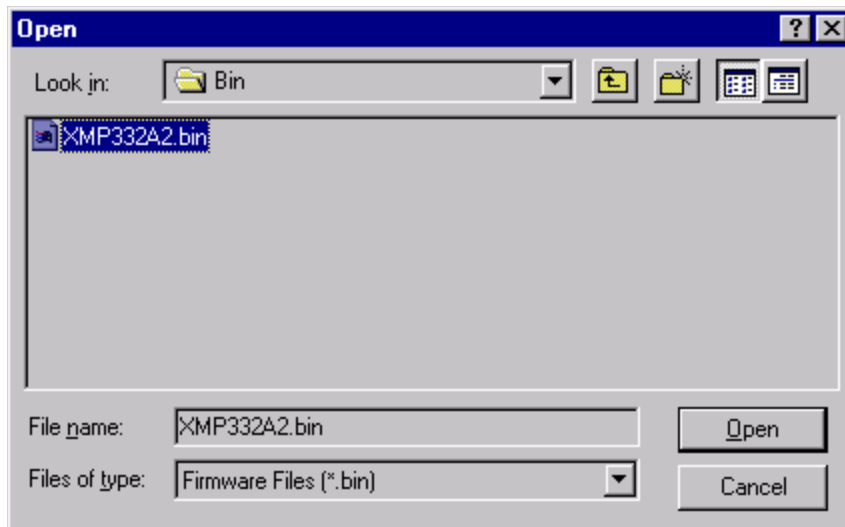
For example, if Motion Console detects that the controller is in the factory default configuration (no firmware) or if the MPI DLL is not compatible with the firmware, it will prompt the user to download firmware:



Click "Yes". Motion Console will then prompt you for the firmware file:



Click "Browse..." and select the appropriate firmware file (.bin). The firmware is stored in the me\l\mp\bin directory (by default):



Select the proper file and click “Open.”



Now download your firmware file by clicking “OK.”

### **Automated Software Configuration**

During your machine development, several different versions of MPI DLLs and/or XMP firmware might be used. You may want to upgrade to new releases to take advantage of new features, MEI may provide custom features or bug patches for previous releases.

During your machine production, you will want to guarantee software configuration consistency. MEI recommends using the InstallShield release package, a third party installer program, or batch scripts to install your application code and MEI’s software onto your machine.

You will also want to guarantee that the controller’s flash memory configuration is consistent. To load the flash, you could automatically download firmware (.bin) and FPGA (.fpg) code during software installation OR during your application initialization. For example, the flash.exe program could be executed from an installer or batch script during software installation. Included in the XMP\Apps directory, is a sample pro-

gram called “initFlash.c” that demonstrates how to read the controller’s firmware/FPGA versions, check if they match the desired configuration, and download the correct versions (if needed).

Also, you can create your own custom firmware file by saving configurations to flash, and uploading the firmware file to your hard drive. The firmware contains a “userVersion” field, so you can keep track of your custom configured files. Using this technique, the firmware can be configured with Motion Console, uploaded to a file (myfirm.bin) and downloaded to future machines using Motion Console, flash.exe or your application.

## **Frequently Asked Questions**

### ***Why do I need to download firmware to my controller?***

Only the machine developer knows which firmware version and configuration works with their application. By downloading firmware directly, you have complete control over your development and release versions.

### ***Why can't MEI download firmware to my controller at the factory?***

MEI can download your firmware, but it is expensive and causes several problems:

- 1) You would need a custom part number for each controller with a different firmware image. Even if you use the same controller hardware in several machines, each version would need to be ordered, purchased, tracked, and stocked separately.
- 2) Changing a firmware image (version or configuration) would require a new part number. This causes transition problems between “old” and “new” parts.
- 3) Repairs and replacements are much more complicated.
- 4) Field upgrades are not possible. Controllers must be returned to the factory to receive new firmware and a new part number.

### ***What if I need to upgrade software in the field?***

If you configure the flash memory as part of your application or installation, then it is very easy to upgrade software and/or firmware in the field. If you do not, then you’ll need to manually update the flash memory.

### ***Can I modify the FPGA (.fpg) files?***

No. These files are binary and do not contain any configuration data.

## **2.5 New UserVersion in MPIControlConfig{...}**

**MPI 538**

A new element, UserVersion has been added to the MPIControlConfig{...} structure. This feature allows the user to mark a firmware image with a user-defineable version number. This was added in version 20010614.

## **2.6 Changed DAC level units to volts**

**MPI 535**

In version 20010622, the DAC level was changed from DAC units to volts. The MEIMotorDacStatus{...} structure contains the DAC level for cmd and aux DACs. meiMotorStatus(...) is used to read the cmd and aux DAC level from the controller.



## 2.7 Addition of Branch identification to Firmware/MPI version MPI704

A new field has been added to the XMP's firmware to identify and differentiate between intermediate branch software revisions. The branch value is represented as a hex number between 0x00000000 and 0xFFFFFFFF. Each digit represents an instance of a branch (0x1 to 0xF). A single digit represents a single branch from a specific version, two digits represent a branch of a branch, three digits represent a branch of a branch of a branch, etc.

## 2.8 Path Motion works with all Interpolation Algorithms MPI660

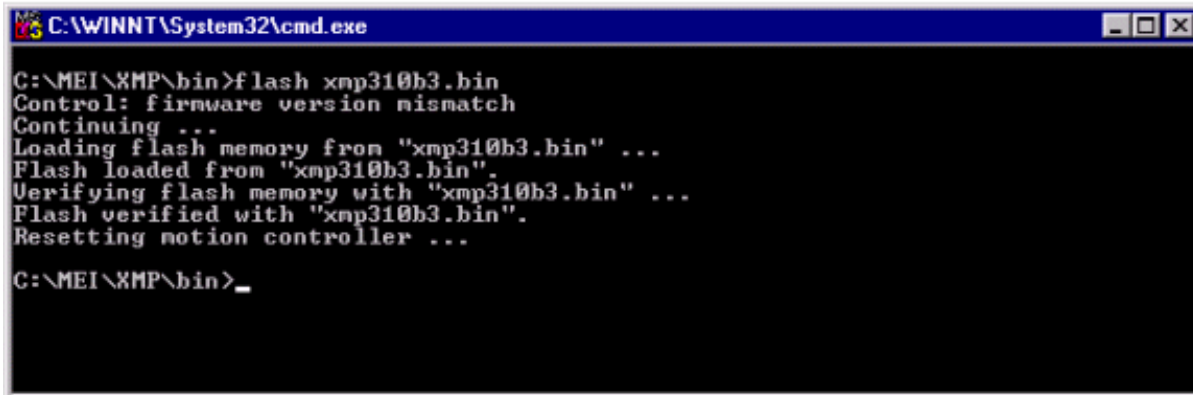
In previous versions, path trajectory generation was only supported by bsplines. Path trajectory generation is now supported by PT, PVT, SPLINE, BESSEL, BSPLINE and BSPLINE2 algorithms. Blending of the corners is only available for the 2 bspline algorithms. Blending of a corner is when the path does not hit the corner but goes through a smooth arc.

## 2.9 Flash Utility Now Supports Flash from File Interface Changes MPI629

The XMP-Series controllers have on-board flash memory to store code and configuration data for the DSP, and fuse maps for the FPGAs. In previous versions, the DSP and FPGA code were stored in a single flash file (XMPxxxxx.bin). Now, the DSP code/data are stored in one file (XMPxxxxx.bin) and the FPGA code is stored in separate files (xxx\_xxxx.fpg). This change was required in order to support several different XMP-Series controller platforms, each with different FPGAs, but all with the same flash memory component. This feature makes it possible to download custom FPGA files.

If your application downloads a Flash file (.bin), you will need to update your application code to download the DSP (.bin) and FPGA (.fpg) code. The flash.exe utility sources demonstrate how to implement this into your application. You must make sure the DSP (.bin) and ALL FPGA (.fpg) files are installed on the host computer for downloading. The FPGA and DSP files must be in the same directory or flash must be called with -FPGAx option, specifying the path to the FPGA file.

Here is the output from the **OLD** flash.exe operation.



```
C:\WINNT\System32\cmd.exe
C:\MEI\XMP\bin>flash xmp310b3.bin
Control: firmware version mismatch
Continuing ...
Loading flash memory from "xmp310b3.bin" ...
Flash loaded from "xmp310b3.bin".
Verifying flash memory with "xmp310b3.bin" ...
Flash verified with "xmp310b3.bin".
Resetting motion controller ...

C:\MEI\XMP\bin>_
```

Here is the **NEW** flash.exe command line options and operation. Notice, that flash.exe automatically determines the XMP hardware configuration and downloads the appropriate .fpg files:

```

C:\WINNT\System32\cmd.exe

C:\MEI\XMP\bin>flash
usage: flash
      [-b(lank all flash)] or
      [-e(rase all flash)] or
      [-s(ave)] [binfile] or
      [<-l(oad)>] filelist ripConfigList

filelist = [binfile] [-FPGA0 file] [-FPGA1 file] [-FPGA2 file]
ripConfigList = [-MB0 number] [-MB1 number] [-20KHZ]

C:\MEI\XMP\bin>

```

### Options

```

C:\WINNT\System32\cmd.exe

C:\MEI\XMP\bin>flash xmp325b2.bin
Control: firmware version mismatch
Continuing ...
Loading flash memory from "xmp325b2.bin" ...
Code loaded and verified from "xmp325b2.bin".
FPGAs loaded and verified from
240_0801.fpg
240_0902.fpg
211_890a.fpg

Configuring RipTide
Reconfigured RipTide:
Main Board has 2 Motion Blocks
Expansion Board has 2 Motion Blocks

Resetting motion controller ...

C:\MEI\XMP\bin>_

```

### Operation

## 2.10 Flash from File Interface Change

**MPI595**

In previous versions, the DSP and FPGA code were stored in a single flash file (XMPxxxxx.bin). Now, the DSP code/data are stored in one file (XMPxxxxx.bin) and the FPGA code is stored in separate files (xxx\_xxxx.fpg). This change was required to support several different XMP-Series controller platforms, each with different FPGAs, but all with the same flash memory component.

To support this change, the "Flash Memory" methods were changed in version 20010216. Here are the changes (from stdmei.h):

```

#define MEIFlashFileMaxNameChars(12)* 8.3 format */
#define MEIFlashFileMaxChars(120)
#define MEIFlashFileMaxPathChars(MEIFlashFileMaxChars - MEIFlashFileMaxNameChars)

typedef struct MEIFlashFiles {
    char binFile[MEIFlashFileMaxChars];
    char FPGAFile[MEIXmpFlashMaxFPGAFiles][MEIFlashFileMaxChars];
} MEIFlashFiles;

```

```

MPI_DECL1 long MPI_DECL2
    meiFlashMemoryFromFileAndVerify(MEIFlash      flash,
                                     MEIFlashFiles *filesIn,
                                     MEIFlashFiles *filesOut);

```

You provide the filesIn with a valid binFile. If the FPGAFiles are NULL, then the MPI Library will automatically generate the default file names for the FPGAs from the hardware info on the board and the path from the binFile. Otherwise, you can specify FPGA files (up to 3 MEIXmpFlashMaxFPGAFiles), including the path. The file order in MEIFlashFiles.FPGAFile[...] is not important. If the file name is not correct or does not match the controller hardware, an error code is returned and the offending file name will be placed in the filesOut (if it is not NULL) structure.

If meiFlashMemoryFromFile(...) returns MPIMessageOK, then filesOut (if it was not NULL) will contain the files and paths of the bin and FPGA files that were loaded and verified. If an error is returned, then filesOut (if it was not NULL) will contain the bin and FPGA files that either were not found or could not be loaded (the error code tells you the result). Internally, the verify is required to update the table in the data portion of the flash image with valid pointers to the FPGA images.

In flash.h, meiFlashMemoryFromFile(...) has been extended to support both binFile and FPGAFile types. meiFlashVerify(...) was removed, but it's functionality was moved into meiFlashMemoryFromFileAndVerify(...).

## 2.11 Dac Object Removed

## MPI628

The Dac object has been removed. The Dac object features have been moved into the Motor object. The Dac numbering has been changed. New methods have been added to write to a Dac's offset and read a Dac's level. The MPIControlConfig structure has been modified to support the new Dac numbering. These changes were required to support new controller models and simplify the MPI.

In previous versions, each Dac object supported a single channel, which was numbered 0, 1, 2, ... 31. The XMP controller can have up to two Dacs per axis. One channel is for standard servo control and the other channel is an auxiliary, OR both channels are used for sinusoidal commutation. The number of enabled Dacs (0 to 32) was configured by specifying the dacCount in the MPIControlConfig{...} structure.

The MEIMotorConfig{...} structure has been extended to include a new MEIMotorDacConfig{...} structure. Each MEIMotorDacConfig{...} structure contains a Cmd and an Aux MEIMotorDacChannelConfig{...} structure:

```

typedef struct MEIMotorDacChannelConfig {
    float          Offset;          /* volts */
    float          Scale;
    MEIXmpDACInputType InputType;
    MEIXmpGenericValue *Input;
} MEIMotorDacChannelConfig;

typedef struct MEIMotorDacConfig {
    MEIXmpDACPhase      Phase;
    MEIMotorDacChannelConfig Cmd;
    MEIMotorDacChannelConfig Aux;
} MEIMotorDacConfig;

```

To read a Dac's offset or write a Dac's offset, use the new methods:

```

meiMotorDacConfigGet(MPIMotor      motor,
                    MEIMotorDacConfig *dacConfig,
                    MEIFlash        flash);

meiMotorDacConfigSet(MPIMotor      motor,
                    MEIMotorDacConfig *dacConfig,
                    MEIFlash        flash);

```

The MEIMotorStatus{...} structure has been extended to include a new MEIMotorDacStatus{...} structure. Each MEIMotorDacStatus{...} structure contains a cmd and an aux MEIMotorDacChannelStatus{...} structure:

```

typedef struct MEIMotorDacChannelStatus {
    float    level; /* volts */
} MEIMotorDacChannelStatus;

typedef struct MEIMotorDacStatus {
    MEIMotorDacChannelStatus  cmd;
    MEIMotorDacChannelStatus  aux;
} MEIMotorDacStatus;

typedef struct MEIMotorStatus {
    MEIMotorDacStatus          dac;
} MEIMotorStatus;

```

To read a Dac's level, use meiMotorStatus(...).

Since the MPI has changed, the Dac numbering is different:

	<b>OLD MPI</b>	<b>NEW MPI</b>	<b>NEW MPI</b>
<b>Hardware Signal</b>	<b>Dac Number</b>	<b>Motor Number</b>	<b>Dac Channel</b>
Cmd_Dac_Out_0	0	0	Cmd
Aux_Dac_Out_0	16	0	Aux
Cmd_Dac_Out_1	1	1	Cmd
Aux_Dac_Out_1	17	1	Aux
Cmd_Dac_Out_2	2	2	Cmd
Aux_Dac_Out_2	18	2	Aux
Cmd_Dac_Out_3	3	3	Cmd
Aux_Dac_Out_3	19	3	Aux
Cmd_Dac_Out_4	4	4	Cmd
Aux_Dac_Out_4	20	4	Aux
Cmd_Dac_Out_5	5	5	Cmd
Aux_Dac_Out_5	21	5	Aux
Cmd_Dac_Out_6	6	6	Cmd

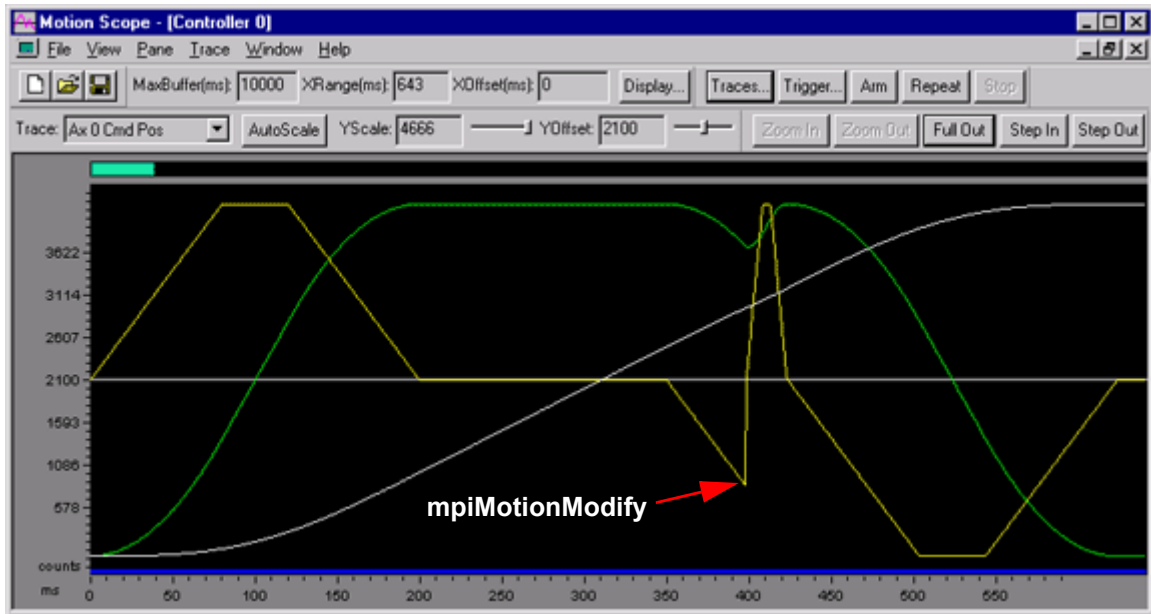
	<b>OLD MPI</b>	<b>NEW MPI</b>	<b>NEW MPI</b>
Aux_Dac_Out_6	22	6	Aux
Cmd_Dac_Out_7	7	7	Cmd
Aux_Dac_Out_7	23	7	Aux
Cmd_Dac_Out_8	8	8	Cmd
Aux_Dac_Out_8	24	8	Aux
Cmd_Dac_Out_9	9	9	Cmd
Aux_Dac_Out_9	25	9	Aux
Cmd_Dac_Out_10	10	10	Cmd
Aux_Dac_Out_10	26	10	Aux
Cmd_Dac_Out_11	11	11	Cmd
Aux_Dac_Out_11	27	11	Aux
Cmd_Dac_Out_12	12	12	Cmd
Aux_Dac_Out_12	28	12	Aux
Cmd_Dac_Out_13	13	13	Cmd
Aux_Dac_Out_13	29	13	Aux
Cmd_Dac_Out_14	14	14	Cmd
Aux_Dac_Out_14	30	14	Aux
Cmd_Dac_Out_15	15	15	Cmd
Aux_Dac_Out_15	31	15	Aux

The MPIControlConfig{...} structure has been changed to include cmdDacCount and auxDacCount. The cmdDacCount specifies the number of enabled Cmd Dacs and auxDacCount specifies the number of enabled Aux Dacs. To configure the number of enabled Dacs, use mpiControlConfigGet/Set(...).

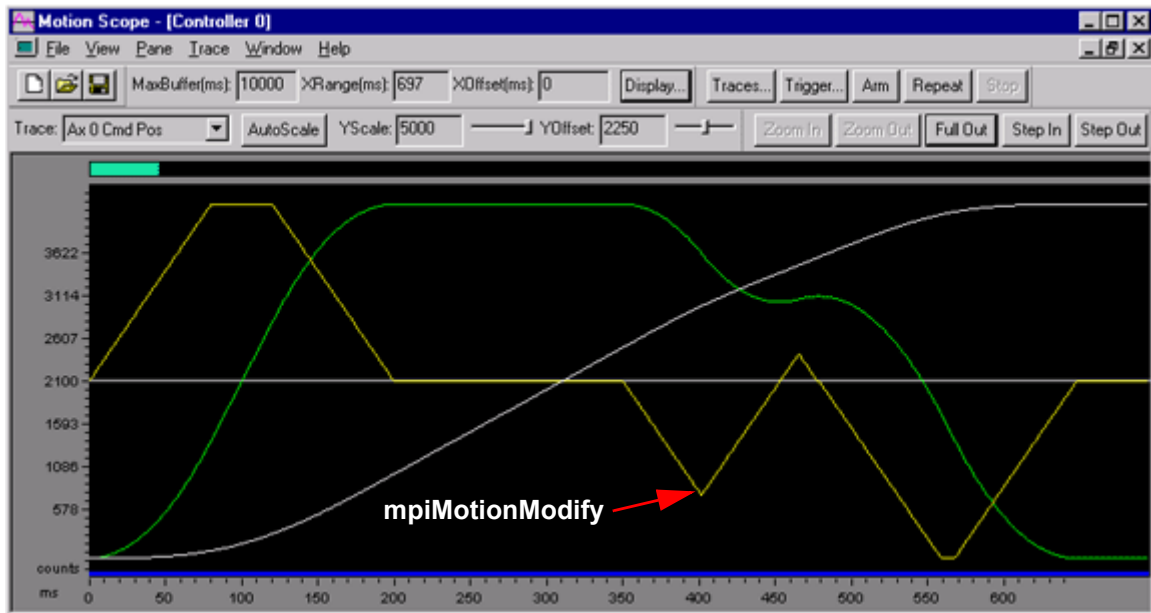
## 2.12 New S-Curve Jerk Algorithm

## MPI615

A new move type, MPIMotionTypeS\_CURVE\_JERK, has been added to support a jerk-specified profile. This replaces the old jerkPercent algorithm. Two added features that the new S-Curve Jerk algorithm provide are the ability to call a motion modify at any time during a path move and the freedom to change jerk, acceleration, and maximum velocity independently. None of these values will be exceeded in the resulting motion. The new S-Curve Jerk algorithm will be ideal for making final adjustments to a move as it draws closer to its final target and for making smoother transitions from one motion to the next.



**Old firmware:** Notice that the acceleration is assumed to be zero and that there is a sudden change in the velocity as a result.



**New Firmware:** Notice that the acceleration changes less abruptly and that the velocity profile is much smoother.

Safe parameters for jerk values should range from a minimum of  $\frac{a_{max} \cdot a_{max}}{v_{max}}$  ( $a_{max}$  is just reached when accelerating from 0 to  $v_{max}$ ) and a maximum of  $\frac{a_{max}}{\text{sample period}}$  ( $a_{max}$  is reached in

one sample period). In the new firmware, changes to the jerk will also change the time needed to complete a motion. For example, a large value of jerk will have a shorter time, but increase the “jerkiness” of the motion (see fig 1). Conversely, a small value of jerk will have a longer time, but a much smoother motion (see fig 2).

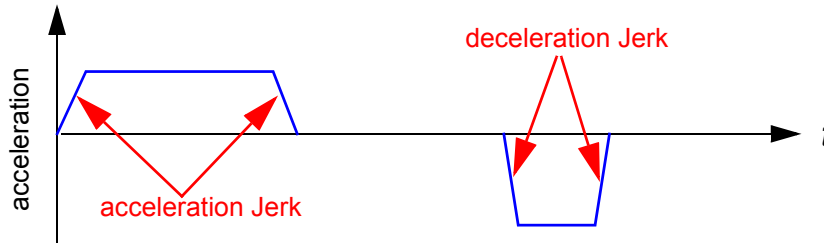


Fig 1. Acceleration profile with **larger** value of jerk.

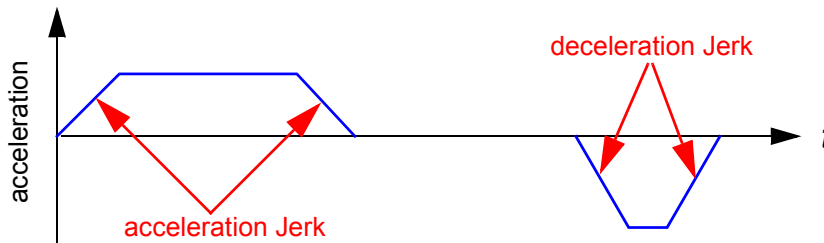


Fig 2. Acceleration profile with **smaller** value of jerk.

Two new parameters, accelerationJerk and decelerationJerk have been added to the MPITrajectory{...} structure. When they are non-zero, the acceleration profile uses the specified jerk and acceleration to ramp an axis(es) to constant velocity and then decelerate to a stop. If accelerationJerk or decelerationJerk is zero, an illegal parameter error is returned.

For the move type, MPIMotionTypeS\_CURVE, the MPI calculates an appropriate jerk value based on the specified velocity, acceleration, and jerkPercent. The jerk value is computed according to the following formula:

$$\text{jerk} = \text{amax} * \text{amax} / (\text{vmax} * \text{jp} * \text{sp} (1 - \text{jp} * \text{sp}))$$

jp = jerkPercent  
sp = sample period

If jerkPercent is zero, the jerk value is computed so that the maximum acceleration is reached in one sample period. With the previous S-Curve algorithm, the time for a move would not change as jerkPercent value was varied. This is also true for this S-Curve algorithm, as long as the move reaches maximum velocity. In short moves, where maximum velocity is not reached, setting jerkPercent to be small will result in a quicker move than if you were to set jerkPercent to be large.

**WARNING!** The same jerkPercent values may cause different profiles than the previous S-Curve algorithm.

For S-Curve algorithm attributes, see section 2.5.

## 2.13 S-Curve Jerk Algorithm Attributes

MPI623

The new S\_Curve algorithm behaves similarly to the previous algorithm, except for its attributes.  
*For a general explanation of the new S-Curve algorithm, see section 2.4.*

**MPIMotionAttrMaskDELAY** can now be used with any start motion, but never with motion modify.

**MPIMotionAttrMaskAPPEND** can be used with any motion, as long as it is not preceded by a motion that had a final velocity.

**MEIMotionAttrMaskNO\_REVERSAL** returns a MPIMotionMessagePROFILE\_ERROR if the given specifications would result in a move with a reversal init, thereby preventing the move from being executed.

### **MPIMotionTypeTRAPEZOIDAL, MPIMotionTypeS\_CURVE, and MPIMotionTypeS\_CURVE\_JERK**

**MPIMotionAttrMaskRELATIVE**, when used with MPIMotionTypeTRAPEZOIDAL, MPIMotionTypeS\_CURVE and MPIMotionTypeS\_CURVE\_JERK means that the final position is relative to the beginning position of the motion.

**MEIMotionAttrMaskFINAL\_VEL** can be used with MPIMotionTypeTRAPEZOIDAL, MPIMotionTypeS\_CURVE and MPIMotionTypeS\_CURVE\_JERK, but should be used with caution as it may not be possible for the controller to compute a trajectory to meet these criteria, which would cause a MPIMotionMessagePROFILE\_ERROR to be returned, and the move to be ignored.

### ***--Multi-Axis Motion--***

#### **Neither MPIMotionAttrMaskSYNC\_START nor MPIMotionAttrMaskSYNC\_END**

If neither MPIMotionAttrMaskSYNC\_START nor MPIMotionAttrMaskSYNC\_END are specified, a single MPITrajectory{...} may be specified for the resultant motion of multiple axes on one motion supervisor. The motion of each axis will be synchronized with the others on the motion supervisor. The maximum velocity, acceleration, deceleration, and jerk values of the first MPITrajectory structure will be used for the global vector parameters. It will ignore any other values supplied. This cannot be used with MEIMotionAttrMaskFINAL\_VEL.

#### **MPIMotionAttrMaskSYNC\_START or MPIMotionAttrMaskSYNC\_END but not both**

If MPIMotionAttrMaskSYNC\_START or MPIMotionAttrMaskSYNC\_END (but not both) is specified, each axis will move as fast as possible and either start together, or stop together. If motion is point-to-point and more than one axis on the motion supervisor has a final velocity, MPIMotionAttrMaskSYNC\_START or MPIMotionAttrMaskSYNC\_END must be used. MPIMotionAttrMaskSYNC\_END cannot be used with motion modify.

#### **Both MPIMotionAttrMaskSYNC\_START and MPIMotionAttrMaskSYNC\_END**

With MPIMotionAttrMaskSYNC\_START and MPIMotionAttrMaskSYNC\_END, the motion for each axis will be scaled so that the motion of all axes will end at approximately the same time. The time for this motion is based on the time for the longest motion, so that the limits are not exceeded. The axes will be scaled to start and stop together, but the scaling may not be exact. Both MPIMotionAttrMaskSYNC\_START and MPIMotionAttrMaskSYNC\_END cannot be used together with MEIMotionAttrMaskFINAL\_VEL.



## **MPIMotionTypeVELOCITY**

MPIMotionTypeVELOCITY moves allow a final velocity to be specified without a final point.

### **MPIMotionAttrMaskSYNC\_START and/or MPIMotionAttrMaskSYNC\_END**

Neither is supported for this motion type. MPIMotionAttrMaskSYNC\_END cannot be used with motion modify.

### **MEIMotionAttrMaskFINAL\_VEL**

MEIMotionAttrMaskFINAL\_VEL is not supported for this motion type.

### **MPIMotionAttrMaskRELATIVE**

MPIMotionAttrMaskRELATIVE, when used with MPIMotionTypeVELOCITY or MPIMotionTypeVELOCITY\_JERK, means that the final velocity is relative to the velocity at the start of the motion.

## **2.14 Configurable Record Buffer Size**

**MPI577**

The Data Recorder buffer size can now be dynamically allocated. The MPIControlConfig{...} structure has a new element, called recordCount. This element allows the application to change the size of the recorder object's data buffer using the mpiControlConfigGet/Set(...) methods. A larger data buffer size can improve the performance of MotionScope running on a slow host or running in Client/Server mode over a congested network.

A new method, meiControlExtMemAvail(...), has been added which will return the size of external memory available for allocation. This value can be added to the current recordCount to expand the record buffer to the maximum possible size.

## **2.15 Dynamic Allocation of External Memory Buffers**

**MPI575**

In previous versions, the XMP external memory was allocated statically at firmware compile time.

In version 20010119 and later, specific buffers of the XMP external memory is dynamically allocated. The dynamic allocation feature allows an application to efficiently use the XMP controller's on-board memory and allows for future expansion. The dynamically allocated buffers currently include the Frame Buffer, Record Buffer and the SERCOS buffer. Each of these buffers sizes are recalculated during a call to mpiControlConfigSet(...) if any of the associated ControlConfig values change.

The Frame Buffer is used for motion on each axis. The Frame Buffer is directly associated with the number of EnabledAxes in the MPIControlConfig structure. The Frame Buffer will be allocated to the minimum size required to support the number of enabled axes. The default number of EnabledAxes is eight (8).

The Record Buffer is used for the on-board data recorder. The Record Buffer is directly associated with the number of EnabledRecord in the MPIControlConfig structure. The Record Buffer will be allocated to the minimum size required to support the number of enabled records. The default number of EnabledRecords is 3064. Each record is the size of one memory word.

The Sercos Buffer is used for motion on each SERCOS ring network. The Sercos Buffer is directly associated with the number of EnabledSercos in the MPIControlConfig structure. The Sercos Buffer will be allo-

cated to the minimum size required to support the number of enabled Sercos rings. The default number of EnabledSercosRings, for a non-sercos controller is zero (0).

A new method has been added to discover how much memory is available on your controller. The method...

```
MPI_DEF1 long MPI_DEF2
    meiControlExtMemAvail(MPIControl control,
                          long *size)
```

...will return the number of memory words available. Since each record size is one memory word, the size returned from the above function can be used to increase the Record Buffer to maximum size possible. This greatly improves client/server operation of Motion Scope and any application used for data collection.

WARNING: Due to the nature of dynamic allocation and the clearing of external memory buffers mpiControlConfigSet(...) should ONLY be called at motion application initialization time and NOT during motion.

## 2.16 mpiAxisActualVelocity argument changed

**MPI546**

In previous releases, the actual velocity argument in mpiAxisActualVelocity(...) was a float. It has been changed to a double for consistency with other MPI methods. This was changed in version 20001130.

## 2.17 mpiAxisPositionError(...) added

**MPI518**

A new method has been added:

```
mpiAxisPositionError(MPIAxis axis
                     double *error);
```

This method is used to retrieve the Position Error from a given axis. A valid instance of MPIAxis is passed to this method along with a pointer to a long variable (long\* error). The method does appropriate error checking on the MPIAxis variable as well as the long \*. Incorrect arguments could return MPIMessageARG\_INVALID or MPIMessageOBJECT\_NOT\_ENABLED. The method then retrieves the PositionError variable from the MEIXmpAxis structure, converts it from a float to a long, and assigns the value to the variable pointed to by the long \* argument. A return value of 0 indicates that the procedure executed without error. This new method was added in version 20001103.

### 3 Incremental Changes

Since the general release of MPI version 20000913, API changes have been made to add features and to fix any bugs encountered. Below is an incremental list of changes that have occurred in later revisions. The incremental changes sections are in reverse order, with the most recent changes first. These changes have been made in a continual effort to provide a better product by incorporating customer feedback and rigorous testing methods. Fixed bugs are treated in Section 5 on page 94. Outstanding bugs and limitations are treated in Section 6 on page 101 of this release note.

*Changes* and *additions* to existing code are indicated in **bold** characters; in electronic media, they are indicated in **bold blue** characters.

*Deletions* are indicated in ~~bold strikethrough~~ characters; in electronic media, they are indicated in ~~bold-red strikethrough~~ characters.

Extended lines of unchanged code are indicated with a vertical, bold ellipses along the left margin:

#### **Version 20020117.1.6.1.3**

In this release, the MPI and firmware versions are:

	<b>Previous Version</b>	<b>New Version</b>
Firmware	371A5	371A5
MPI Library	20020117.1.6.1.2	20020117.1.6.1.3

- A bug (MPI1816) where calls to mpiMotorEventConfigGet(...) and mpiMotorConfigSet(...) from more than one thread, for the same motor object would cause incorrect "Arg Invalid" errors to be returned has been fixed. Please see Section 5 of this release note for more information.

#### **Version 20020117.1.6.1.2**

In this release, the MPI and firmware versions are:

	<b>Previous Version</b>	<b>New Version</b>
Firmware	371A5	371A5
MPI Library	20020117.1.6.1.1	20020117.1.6.1.2

- A bug (MPI1720) where the startup script did not work when the console cable was disconnected has been fixed. Please see Section 5 of this release note for more information.

#### **Version 20020117.1.6.1.1**

In this release, the MPI and firmware versions are:

	<b>Previous Version</b>	<b>New Version</b>
Firmware	371A5	371A5
MPI Library	20020117.1.6	20020117.1.6.1.1

- A bug (MPI1507) in the VxWorks compiler caused positions greater than  $2^{31}$  to get truncated has been fixed. Please see Section 5 of this release note for more information.

## Version 20020117.1.6

In this release, the MPI and firmware versions are:

	Previous Version	New Version
Firmware	364A3	371A5
MPI Library	20020117.1.3	20020117.1.6

- Multiple Injection Point Noise Source has been added to the xmp firmware. Please see Section 2.1 of this general release note for more information.
- Changes have been made to streamline the loading of points lists. Please see Section 2.2 of this general release note for more information.
- (MPI903) Two changes were made to the compensation table calculations to eliminate the immediate toggling of the compensation value on either side of a maximum compensation value in the compensation table. Please see Section 5 of this release note for more information.
- A bug (MPI895) where sim4calc.exe could calculate incorrect look-up tables has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI888) where PVT moves would produce duplicate points at the transition of Element IDs has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI887) in multi-point motion (i.e. PVT, PT, spline, etc), which could cause intermittent Memory Access Violation errors has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI885) where changing sample rates could cause unexpected motor faults has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI884) where the MPI would misinterpret the axis's state and report a Stopping Error has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI881) where the meiFlashMemoryVerify(...) would fail if the entire image was compared to a list of host files has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI879) where mpiFilterConfigSet(...) would improperly return a MPIMessagePARAM\_INVALID error if the Algorithm was PIV and the PostFilter.Length was non-zero has been fixed. Please see Section 5 of this release note for more information.
- A typo (MPI843) in the mpiControlInit(...) macro definition, which caused compilation errors has been fixed. Please see Section 5 of this release note for more information.

## Version 20020117.1.3

In this release, the MPI and firmware versions are:

	Previous Version	New Version
Firmware	358A2	364A3
MPI Library	20020117.1	20020117.1.3

- A bug (MPI829) where an improperly commented block of code caused a shortening of the step pulse by 1/4 has been fixed. Please see Section 5 of this release note for more information.
- A limitation (MPI836) exists where an overshoot will occur when a motion modify is called under certain conditions. Please see Section 6.2 of this general release note for more information.

## Version 20020117.1

In this release, the MPI and firmware versions are:

	Previous Version	New Version
Firmware	358A2	358A2
MPI Library	20020117	20020117.1

## Version 20020117

In this release, the MPI and firmware versions are:

	Previous Version	New Version
Firmware	347B1	358A2
MPI Library	20011213	20020117

- MEI's new On-Line Documentation System is now available. You can access the web site at <http://support.motioneng.com> or through the Install Shield CD-ROM. Please see Section 2.3 of this general release note for more information.
- There is a new default XMP-Series Controller Configuration. The XMP-Series controller's Flash memory is now pre-loaded at the factory with base firmware. This firmware allows the MPI to identify the XMP-Series controller. Please see Section 2.4 of this general release note for more information.
- A new element, UserVersion has been added to the MPIControlConfig{...} structure. Please see Section 2.5 of this general release note for more information.
- The DAC level has changed from DAC units to volts. Please see Section 2.6 of this general release note for more information.
- A bug (MPI767) that caused a Device Driver port call failure has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI737) that was caused by incorrect handling of the UPDATE frame has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI735) where the IN\_FINE criteria was only checked in the STOPPED state has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI734) which caused mpiMotionStart() calls occurring right after a DONE event to cause a MOVING error has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI691) where an erroneous TIMEOUT return value was returned from mpiMotorEvent-ConfigSet(...) has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI581) where an incorrect error was returned with mpiMotorStatus(...) and meiMotorStatus(...) has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI528) where mpiAxisCommandPositionSet(...) would not set the command position if the axis was in the Stop condition has been fixed. Please see Section 5 of this release note for more information.
- A bug (23) where mpiControlReset(...) would return too early, causing MPI methods to fail has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI632) where there was a FrameBuffer referencing error has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI586) where performing a MPIActionStop after a MPIActionReset caused an error has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI625) where executing the flash utility with the server option failed has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI573) where changes made to mpiMotorIoSet(...) could be erased because of Riptide latencies has been fixed. Please see Section 5 of this release note for more information.

- A bug (MPI544) where there was no action synchronization between the MPI and firmware causing the MPI to read old values has been fixed. Please see Section 5 of this release note for more information.

## **Version 20011213**

In this release, the MPI and firmware versions are:

	<b>Previous Version</b>	<b>New Version</b>
Firmware	325B2	347B1
MPI Library	20010417.1	20011213

- A new field has been added to the XMP's firmware to identify and differentiate between intermediate branch software revisions. Please see Section 2.7 of this general release note for more information.
- Path trajectory generation is now supported by PT, PVT, SPLINE, BESSEL, BSPLINE and BSPLINE2 algorithms. Please see Section 2.8 of this general release note for more information.
- A bug (MPI769) where there was a problem caused by an improper error check in the mpiMotionModify(...) has been fixed. Please see Section 5 of this release note for more information.
- A bug (MPI713) where mpiRecorderRecordGet(...) returned corrupted data has been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 697) where improper interaction occurred between the mpiMotionModify(...) and command position has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 688) where mpiMotorConfigGet() would return an error if both the MPIMotorConfig and MEIMotorConfig structures were passed has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 686) where there was in incorrect motion profile with mpiMotionModify(...) has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 683) mpiMotionModify(...) would cause a trajectory discontinuity with velocity type moves has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 672) where the filter coefficient value for DRate was being incorrectly saved has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 659) where mpiControlReset(...) could lock up the PCI bus has now been fixed. Please see Section 5 of this general release note for more information.
- A bug (MPI 741) exists where the Win2000 device driver will not allow a host system to go into "Standby" mode. Please see Section 6 for more information.
- A limitation (MPI 703) exists where the Filter object's DRate (derivative sub-sampling rate) is limited to a range from 0 to 7. Please see Section 6.2 for more information.

## Version 20010417.1

In this release, the MPI and firmware versions are:

	Previous Version	New Version
Firmware	310B3	325B2
MPI Library	2000091302	20010417.1

### Changes to MPI/XMP Header Files

- **Changes to # defines (“control.h” header file)**

```
#define MPI_VERSION    "20020117"  
  
#define MPIControlUserIoSizeINPUT    (2)  
#define MPIControlUserIoSizeOUTPUT  (2)  
#define MPIControlUserIoSizeCONFIG  (2)
```

- **Changes to MPIAxisMessage data type (“axis.h” header file)**

```
typedef enum {  
    MPIAxisMessageFIRST = mpiMessageID(MPIModuleIdAXIS, 0),  
  
    MPIAxisMessageAXIS_INVALID,  
    MPIAxisMessageCOMMAND_NOT_SET,  
  
    MPIAxisMessageLAST  
} MPIAxisMessage;
```

- **Changes to MPICommandMessage data type (“command.h” header file)**

```
typedef enum {  
    MPICommandMessageFIRST = mpiMessageID(MPIModuleIdCOMMAND, 0),  
  
    MPICommandMessageCOMMAND_INVALID,  
    MPICommandMessageTYPE_INVALID,  
    MPICommandMessagePARAM_INVALID,  
  
    MPICommandMessageLAST  
} MPICommandMessage;
```

- **Changes to #defines (“control.h” header file)**

```
#define MPI_VERSION    "20010828"  
  
#define MPIControlUserIoSizeINPUT    (2)  
#define MPIControlUserIoSizeOUTPUT  (2)  
#define MPIControlUserIoSizeCONFIG  (2)
```

- **Changes to MPIControlConfig data type (“control.h” header file)**

```
typedef struct MPIControlConfig {
    long   adcCount;
    long   axisCount;
    long   captureCount;
    long   compareCount;
    long   cmdDacCount;
    long   auxDacCount;
    long   filterCount;
    long   motionCount;
    long   motorCount;
    long   recordCount;
    long   sequenceCount;
    long   sercosCount;
    long   userVersion;
    long   sampleRate;
    MPIControlUserIoConfig userIoConfig;
    MPIControlUserIo userIo;
} MPIControlConfig;
```

- **Changes to MPIControlMessage data type (“control.h” header file)**

```
typedef enum {
    MPIControlMessageFIRST = mpiMessageID(MPIModuleIdCONTROL, 0),

    MPIControlMessageLIBRARY_VERSION, /* Keep as first control message */
    MPIControlMessageADDRESS_INVALID,
    MPIControlMessageCONTROL_INVALID,
    MPIControlMessageType_INVALID,
    MPIControlMessageINTERRUPTS_DISABLED,
    MPIControlMessageEXTERNAL_MEMORY_OVERFLOW,
    MPIControlMessageADC_COUNT_INVALID,
    MPIControlMessageAXIS_COUNT_INVALID,
    MPIControlMessageCAPTURE_COUNT_INVALID,
    MPIControlMessageCOMPARE_COUNT_INVALID,
    MPIControlMessageCMDDAC_COUNT_INVALID,
    MPIControlMessageAUXDAC_COUNT_INVALID,
    MPIControlMessageFILTER_COUNT_INVALID,
    MPIControlMessageMOTION_COUNT_INVALID,
    MPIControlMessageMOTOR_COUNT_INVALID,
    MPIControlMessageLAST
} MPIControlMessage;
```

- **Deletion of mpiControlUserIoConfigGet method (“control.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiControlUserIoConfigGet(MPIControl
                             MPIControlUserIoConfig
                             control,
                             &userIoConfig);
```

- **Deletion of mpiControlUserIoConfigSet method (“control.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiControlUserIoConfigSet(MPIControl
                              MPIControlUserIoConfig
                              control,
                              &userIoConfig);
```

- **Deletion of mpiControlUserIoGet method (“control.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiControlUserIoGet(MPIControl
                       -MPIControlUserIo
                       control,
                       &userIo);
```



- Deletion of mpiControlUserIoSet method (“control.h” header file)

```
MPI_DECL1 long MPI_DECL2
mpiControlUserIoSet(MPIControl          control,
                    MPIControlUserIo    *userIo);
```

- Changes to MPIMotionMessage data type (“motion.h” header file)

```
typedef enum {
    MPIMotionMessageFIRST = mpiMessageID(MPIModuleIDMOTION, 0),

    MPIMotionMessageMOTION_INVALID,
    MPIMotionMessageAXIS_NOT_FOUND,
    MPIMotionMessageAXIS_COUNT,
    MPIMotionMessageTYPE_INVALID,
    MPIMotionMessageATTRIBUTE_INVALID,
    MPIMotionMessageNOT_READY,
    MPIMotionMessageIDLE,
    MPIMotionMessageMOVING,
    MPIMotionMessageSTOPPING,
    MPIMotionMessageSTOPPING_ERROR,
    MPIMotionMessageERROR,
    MPIMotionMessageAUTO_START,
    MPIMotionMessagePROFILE_ERROR,
    MPIMotionMessagePATH_ERROR,
    MPIMotionMessageFRAMES_LOW,
    MPIMotionMessageFRAMES_EMPTY,

    MPIMotionMessageLAST
} MPIMotionMessage;
```

- Changes to MPIPathElementType data type (“path.h” header file)

```
typedef enum {
    MPIPathElementTypeINVALID = -1,

    MPIPathElementTypeARC,           /* only 2D */
    MPIPathElementTypeARC_CENTER,   /* only 2D */
    MPIPathElementTypeARC_END_POINT, /* both 2D and 3D */
    MPIPathElementTypeHELIX,        /* not currently supported */
    MPIPathElementTypeO,            /* not currently supported */
    MPIPathElementTypeLINE,         /* both 2D and 3D */

    MPIPathElementTypeLAST,
    MPIPathElementTypeFIRST= MPIPathElementTypeINVALID + 1,
    MPIPathElementTypeMASK= 0xFF,
} MPIPathElementType;
```

- Changes to MPIPathElementAttrMask data type (“path.h” header file)

```
typedefenum {
    MPIPathElementAttrMaskRELATIVE = mpiPathElementAttrMaskBIT(MPIPathElementAttrRELATIVE),
    MPIPathElementAttrMaskID       = mpiPathElementAttrMaskBIT(MPIPathElementAttrID),
    MPIPathElementAttrMaskVELOCITY = mpiPathElementAttrMaskBIT(MPIPathElementAttrVELOCITY),
    MPIPathElementAttrMaskACCEL    = mpiPathElementAttrMaskBIT(MPIPathElementAttrACCEL),
    MPIPathElementAttrMaskTIMESLICE = mpiPathElementAttrMaskBIT(MPIPathElementAttrTIMESLICE),

    MPIPathElementAttrMaskALL      = -1 << MPIPathElementAttrFIRST,
} MPIPathElementAttrMask;
```

- **Changes to MPIPathElementAttributes data type (“path.h” header file)**

```
typedef struct MPIPathElementAttributes {
    long    id;                /* MPIPathAttrID*/
    double  velocity;         /* MPIPathAttrVELOCITY*/
    double  acceleration;     /* MPIPathAttrACCELERATION*/
    double  timeSlice;        /* MPIPathAttrTIMESLICE*/
} MPIPathElementAttributes;
```

- **Changes to MPIPathMessage data type (“path.h” header file)**

```
typedef enum {
    MPIPathMessageFIRST = mpiMessageID(MPIModuleIdPATH, 0),

    MPIPathMessagePATH_INVALID,
    MPIPathMessageILLEGAL_DIMENSION,
    MPIPathMessageILLEGAL_ELEMENT,
    MPIPathMessageARC_ILLEGAL_DIMENSION,
    MPIPathMessageHELIX_ILLEGAL_DIMENSION,
    MPIPathMessageILLEGAL_RADIUS,
    MPIPathMessagePATH_TOO_LONG,
    MPIPathMessageILLEGAL_VELOCITY,
    MPIPathMessageILLEGAL_ACCELERATION ,
    MPIPathMessageILLEGAL_TIMESLICE ,
    MPIPathMessageINVALID_BLENDING,

    MPIPathMessageLAST
} MPIPathMessage;
```

- **Change to mpiAxisActualVelocity method (“axis.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiAxisActualVelocity(MPIAxis    axis,
                        double        *actual);
```

- **Addition of mpiAxisPositionError method (“axis.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiAxisPositionError(MPIAxis    axis,
                        double        *error);
```

- **Change to MPICommandParams data type (“command.h” header file)**

```
typedef union {
    struct { /* **dst' = 'value' */
        MPICommandAddress    dst;
        MPICommandConstant   value;
        MPIControl            control; /* Ignored by Sequence */
    } assign;
};
```

- **Change to MPIControlConfig data type (“control.h” header file)**

```
typedef struct MPIControlConfig {
    long    adcCount;
    long    axisCount;
    long    captureCount;
    long    compareCount;
    long    cmdDacCount;
    long    auxDacCount;
    long    filterCount;
    long    motionCount;
    long    motorCount;
    long    recordCount;
    long    sequenceCount;
    long    sercosCount;

    long    sampleRate;

    MPIControlUserIoConfiguserIoConfig;
    MPIControlUserIo    userIo;
} MPIControlConfig;
```

- **Change to MPIControlMessage data type (“control.h” header file)**

```
typedef enum {
    MPIControlMessageFIRST = mpiMessageID(MPIModuleIdCONTROL, 0),
    MPIControlMessageLIBRARY_VERSION, /* Keep as first control message */
    MPIControlMessageADDRESS_INVALID,
    MPIControlMessageCONTROL_INVALID,
    MPIControlMessageTYPE_INVALID,
    MPIControlMessageINTERRUPTS_DISABLED,
    MPIControlMessageEXTERNAL_MEMORY_OVERFLOW,

    MPIControlMessageLAST
} MPIControlMessage;
```

- **Change to MPIFilterMessage data type (“filter.h” header file)**

```
typedef enum {
    MPIFilterMessageFIRST = mpiMessageID(MPIModuleIdFILTER, 0),

    MPIFilterMessageFILTER_INVALID,
    MPIFilterMessageINVALID_ALGORITHM,

    MPIFilterMessageLAST
} MPIFilterMessage;
```

- **Addition of mpiFilterIntegratorReset method (“filter.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    mpiFilterIntegratorReset(MPIFilter filter);
```

- **Change to MPIMotionType data type (“motion.h” header file)**

```
typedef enum {
    MPIMotionTypeINVALID = -1,

    MPIMotionTypeJOG,

    MPIMotionTypePT,
    MPIMotionTypePVT,
    MPIMotionTypeSPLINE,
    MPIMotionTypeBESSEL,
    MPIMotionTypeBSPLINE,
    MPIMotionTypeBSPLINE2,

    MPIMotionTypeS_CURVE,
    MPIMotionTypeTRAPEZOIDAL,
    MPIMotionTypeS_CURVE_JERK,

    MPIMotionTypeVELOCITY,
    MPIMotionTypeVELOCITY_JERK,

#ifdef
    /* Reserved for future use */
    MPIMotionTypeCOORD_ARC,
    MPIMotionTypeCOORD_ARC_FINAL_RADIUS,
    MPIMotionTypeCOORD_HELICAL,
    MPIMotionTypeCOORD_LINEAR,

    MPIMotionTypePARABOLIC,

#endif

    MPIMotionTypeLAST,
    MPIMotionTypeFIRST= MPIMotionTypeINVALID + 1,
    MPIMotionTypeMASK= 0xFF,
} MPIMotionType;
```

- **Addition of MPIMotionSCurveJerk data type (“motion.h” header file)**

```
typedef MPIMotionSCurve    MPIMotionSCurveJerk;
```

- **Change to MPIMotionParams data type (“motion.h” header file)**

```
typedefstruct MPIMotionParams {
    MPIMotionJog          jog;

    MPIMotionPT           pt;
    MPIMotionPVT          pvt;
    MPIMotionSPLINE       spline;
    MPIMotionBESSEL       besse;
    MPIMotionBSPLINE      bspline;

    MPIMotionSCurve       sCurve;
    MPIMotionSCurve       sCurveJerk;
    MPIMotionTrapezoidal  trapezoidal;

    MPIMotionVelocity    velocity;
    MPIMotionVelocity    velocityJerk;

    MPIMotionAttributes  attributes;

    void                 *external;
} MPIMotionParams;
```

- Deletion of MPIMotorDac data type (“motor.h” header file)

```
#define MPIMotorDacCountMAX(sizeof(MPIObjectMap) * 8)

typedef struct MPIMotorDac {
    long    count;
    long    number[MPIMotorDacCountMAX];
} MPIMotorDac;
```

- Change to MPIMotorConfig data type (“motor.h” header file)

```
typedef struct MPIMotorConfig {
    MPIMotorType    type;

    /* Event configuration, ordered by MPIEventType */
    MPIMotorEventConfigevent[MPIEventTypeMOTOR_LAST];

    long    ampEnablePolarity;    /* FALSE => active lo, else active hi */
    long    encoderPhase;        /* 0 => normal, else reversed */
    long    captureOnChange;     /* 0 => normal, else enabled */

    float    abortDelay;
    float    brakeDelay;
    float    enableDelay;

    MPIObjectMap    filterMap;
    MPIObjectMap    adcMap;
    MPIMotorDac    dac;

    MPIMotorIo    io;
} MPIMotorConfig;
```

- Deletion of mpiMotorDacGet method (“motor.h” header file)

```
MPI_DECL1 long MPI_DECL2
mpiMotorDacGet(MPIMotor motor,
               long    *count,
               long    *number);
```

- Deletion of mpiMotorDacMapGet method (“motor.h” header file)

```
MPI_DECL1 long MPI_DECL2
mpiMotorDacMapGet(MPIMotor motor,
                  MPIObjectMap *map);
```

- Deletion of mpiMotorDacSet method (“motor.h” header file)

```
MPI_DECL1 long MPI_DECL2
mpiMotorDacSet(MPIMotor motor,
               long    count,
               long    *number);
```

- **Change to MPIModuleID data type (“mpidef.h” header file)**

```
typedef enum {
    MPIModuleIDINVALID = -1,

    MPIModuleIDMESSAGE,
    MPIModuleIDADC,
    MPIModuleIDAXIS,
    MPIModuleIDCAPTURE,
    MPIModuleIDCOMMAND,
    MPIModuleIDCOMPARE,
    MPIModuleIDCONTROL,
    MPIModuleIDDAC,
    MPIModuleIDEVENT,
    MPIModuleIDEVENTMGR,
    MPIModuleIDFILTER,
    MPIModuleIDIDN,
    MPIModuleIDIDNLIST,
    MPIModuleIDMOTION,
    MPIModuleIDMOTOR,
    MPIModuleIDNODE,
    MPIModuleIDNOTIFY,
    MPIModuleIDPATH,
    MPIModuleIDPROGRAM,
    MPIModuleIDRECORDER,
    MPIModuleIDSEQUENCE,
    MPIModuleIDSERCOS,

    MPIModuleIDLAST,
    MPIModuleIDFIRST = MPIModuleIDINVALID + 1,

    MPIModuleIDEXTERNAL = 0x80,

    MPIModuleIDMAX = 0xFF
} MPIModuleID;
```

- **Change to MPITrajectory data type (“mpidef.h” header file)**

```
typedef struct MPITrajectory {
    double    velocity;
    double    acceleration;
    double    deceleration;
    double    jerkPercent;
    double    accelerationJerk;
    double    decelerationJerk;
} MPITrajectory;
```

- Addition of MPIPathParams data type (“path.h” header file)

```

#if 1
/*
 * PathConfig deprecated in favor of PathParams.
 * WARNING: These definitions will eventually be removed.
 */
#defineMPIPathConfig MPIPathParams
#definempiPathConfigGetmpiPathParamsGet
#definempiPathConfigSetmpiPathParamsSet
#endif

typedef struct MPIPathParams {
    long          dimension;
    MPIPathPointstart;
    double        velocity;
    double        acceleration;
    double        deceleration;
    MPIMotionTypeinterpolation;
    double        timeSlice;
    double        conversion[MPIPathPointDIMENSION_MAX][MPIPathPointDIMENSION_MAX];
} MPIPathParams;

```

- Deletion of mpiPathConfigGet method (“path.h” header file)

```

MPI_DECL1 long MPI_DECL2
mpiPathParamsGet(MPIPath      path,
                  MPIPathParams *params,
                  void          *external);

```

- Deletion of mpiPathConfigSet method (“path.h” header file)

```

MPI_DECL1 long MPI_DECL2
mpiPathConfigSet(MPIPath      path,
                  MPIPathConfig *config,
                  void          *external);

```

- Addition of mpiPathParamsGet method (“path.h” header file)

```

MPI_DECL1 long MPI_DECL2
mpiPathParamsGet(MPIPath      path,
                  MPIPathParams *params,
                  void          *external);

```

- Addition of mpiPathParamsSet method (“path.h” header file)

```

MPI_DECL1 long MPI_DECL2
mpiPathParamsSet(MPIPath      path,
                  MPIPathParams *params,
                  void          *external);

```

- Change to mpiPathParamsSet method (“path.h” header file)

```

MPI_DECL1 long MPI_DECL2
mpiPathParamsSet(MPIPath      path,
                  MPIPathParams *params,
                  void          *external);

```

- Change to MPIRecorderADDRESS\_COUNT\_MAX constant (“recorder.h” header file)

```

#defineMPIRecorderADDRESS_COUNT_MAX    (128)

```

## **Changes to MEI/XMP Header Files**

- **Addition of meiPlatformAssertSet method (“platform.h” header file)**

```
MPI_DEF1 void MPI_DEF2  
meiPlatformAssertSet(void (MPI_DECL2 *func) (const char *file, long line));
```

- **Changes to MEIRemoteMethod data type (“remote.h” header file)**

```
typedef enum {  
    MEIRemoteMethodINVALID = -1,  
  
    MEIRemoteMethodBOARD_TYPE,  
    MEIRemoteMethodBOARD_INFO_GET,  
    MEIRemoteMethodBOARD_INFO_SET,  
  
    MEIRemoteMethodFLASH_MEMORY_GET,  
    MEIRemoteMethodFLASH_MEMORY_SET,  
  
    MEIRemoteMethodINTERRUPT_ENABLE,  
    MEIRemoteMethodINTERRUPT_WAIT,  
    MEIRemoteMethodINTERRUPT_WAKE,  
  
    MEIRemoteMethodMEMORY,  
  
    MEIRemoteMethodMEMORY_GET,  
    MEIRemoteMethodMEMORY_SET,  
  
    MEIRemoteMethodPORT_IN_CHAR,  
    MEIRemoteMethodPORT_OUT_CHAR,  
  
    MEIRemoteMethodOBJECT_LOCK_GIVE,  
    MEIRemoteMethodOBJECT_LOCK_TAKE,  
  
    MEIRemoteMethodRESET,  
  
    MEIRemoteMethodLAST,  
    MEIRemoteMethodFIRST = MEIRemoteMethodINVALID + 1  
} MEIRemoteMethod;
```

- **Addition of MEIRemoteMethodPortInChar data type (“remote.h” header file)**

```
typedef struct MEIRemoteMethodPortInChar {  
    unsigned short port;  
    unsigned char *value;  
} MEIRemoteMethodPortInChar;
```

- **Addition of MEIRemoteMethodPortOutChar data type (“remote.h” header file)**

```
typedef struct MEIRemoteMethodPortOutChar {  
    unsigned short port;  
    unsigned char value;  
} MEIRemoteMethodPortOutChar;
```

- **Changes to MEIRemoteMethodArgs data type (“remote.h” header file)**

```
typedef union {  
    MEIPlatformBoardType*boardType;  
    MEIRemoteMethodBoardInfoGetboardInfoGet;  
    MEIRemoteMethodBoardInfoSetboardInfoSet;
```



```

union {
    long                enable;
    MEIRemoteMethodInterruptWait    wait;
} interruptArgs;
MEIRemoteMethodMemory        memory;
MEIRemoteMethodMemoryGet    memoryGet;
MEIRemoteMethodMemorySet    memorySet;
MEIRemoteMethodPortInChar    portIn;
MEIRemoteMethodPortOutChar    portOut;
MEIRemoteMethodObjectLockGive    objectLockGive;
MEIRemoteMethodObjectLockTake    objectLockTake;
} MEIRemoteMethodArgs;

```

- **Changes to MEIRemoteHeader data type (“remote.h” header file)**

```

typedef struct MEIRemoteHeader {
    unsigned longsize; /* bytes */
    unsigned longsequence;

    MEIRemoteType;
    union {
        struct {
            MEIRemoteMethod        method;
            MEIRemoteMethodArgs    args;
        } query;
        struct {
            long                returnValue;
            union {
                MEIPlatformBoardType    boardType; /* meiPlatformBoardType() */
                unsigned                char    portValue;
                long                interrupted; /* mpiControlInterruptWait() */
                struct {
                    void                *firmware;
                    void                *external;
                } memory; /* mpiControlMemory() */
            } output;
        } reply;
    } asa;

    unsigned longmemory; /* mpiControlMemory[GS]et(count == 4) */
} MEIRemoteHeader;

```

- **Changes to # defines (“xmp.h” header file)**

```

/* #defines and enums */

#define MEIXmpVERSION            358
    /* version, 200 = 2.00 */
#define MEIXmpOPTION            0
    /* FPGA Revision Number */
#define MEIXmpFPGAMBREV        242
#define MEIXmpFPGASIM4REV        211

```

- **Changes to MEIXmpEvent data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpEventIN_COARSE_POSITION    = 0,
    MEIXmpEventAT_TARGET,
    MEIXmpEventAT_VELOCITY,
    MEIXmpEventIN_FINE_POSITION,
    MEIXmpEventDONE,
    MEIXmpEventPPI,
    MEIXmpEventPS_FAULT,
    MEIXmpEventMS_FAULT,
}

```

```

MEIXmpEventOUT_OF_FRAMES,
MEIXmpEventEXTERNAL,
MEIXmpEventFRAME,
MEIXmpEventRESET,
MEIXmpEventRESUME,
MEIXmpEventPAUSE,
MEIXmpEventSTOP,
MEIXmpEventESTOP,
MEIXmpEventESTOP_ABORT,
MEIXmpEventABORT,
MEIXmpEventHOST,
MEIXmpEventRESERVED0,
MEIXmpEventRESERVED1,
MEIXmpEventRESERVED2,
MEIXmpEventREC_IDLE,
MEIXmpEventREC_FULL,
MEIXmpEventREC_RUNNING,
MEIXmpEventLIMIT
= 31,

```

```

} MEIXmpEvent;

```

- **Changes to MEIXmpStatus data type (“xmp.h” header file)**

```

typedef enum {
MEIXmpStatusIN_COARSE_POSITION      = (1 << MEIXmpEventIN_COARSE_POSITION), /* 0x00000001 */
MEIXmpStatusAT_TARGET               = (1 << MEIXmpEventAT_TARGET),          /* 0x00000002 */
MEIXmpStatusAT_VELOCITY             = (1 << MEIXmpEventAT_VELOCITY),        /* 0x00000004 */
MEIXmpStatusIN_FINE_POSITION        = (1 << MEIXmpEventIN_FINE_POSITION),   /* 0x00000008 */

MEIXmpStatusSETTLED                 = MEIXmpStatusIN_FINE_POSITION,         /* 0x00000008 */
MEIXmpStatusDONE_MASK               = (MEIXmpStatusSETTLED |               /* 0x0000000A */
MEIXmpStatusAT_TARGET),

MEIXmpStatusDONE                    = (1 << MEIXmpEventDONE),              /* 0x00000010 */
MEIXmpStatusIN_FINE_POSITION_LATCHED = MEIXmpStatusDONE,                  /* 0x00000010 */
MEIXmpStatusPPI                     = (1 << MEIXmpEventPPI),               /* 0x00000020 */
MEIXmpStatusPS_FAULT                = (1 << MEIXmpEventPS_FAULT),          /* 0x00000040 */
MEIXmpStatusMS_FAULT                = (1 << MEIXmpEventMS_FAULT),          /* 0x00000080 */
MEIXmpStatusOUT_OF_FRAMES           = (1 << MEIXmpEventOUT_OF_FRAMES),     /* 0x00000100 */
MEIXmpStatusEXTERNAL                = (1 << MEIXmpEventEXTERNAL),          /* 0x00000200 */
MEIXmpStatusFRAME                   = (1 << MEIXmpEventFRAME),            /* 0x00000400 */
MEIXmpStatusRESET                   = (1 << MEIXmpEventRESET),            /* 0x00000800 */
MEIXmpStatusRESUME                   = (1 << MEIXmpEventRESUME),           /* 0x00001000 */

MEIXmpStatusPAUSE                   = (1 << MEIXmpEventPAUSE),             /* 0x00002000 */
MEIXmpStatusSTOP                    = (1 << MEIXmpEventSTOP),              /* 0x00004000 */
MEIXmpStatusESTOP                   = (1 << MEIXmpEventESTOP),            /* 0x00008000 */
MEIXmpStatusESTOP_ABORT             = (1 << MEIXmpEventESTOP_ABORT),       /* 0x000010000 */
MEIXmpStatusABORT                   = (1 << MEIXmpEventABORT),            /* 0x000020000 */

MEIXmpStatusERROR_MASK              = (MEIXmpStatusESTOP |                 /* 0x00038000 */
MEIXmpStatusESTOP_ABORT |
MEIXmpStatusABORT),

MEIXmpStatusHOST                    = (1 << MEIXmpEventHOST),              /* 0x00040000 */

MEIXmpStatusRESERVED0               = (1 << MEIXmpEventRESERVED0),         /* 0x00080000 */
MEIXmpStatusRESERVED1               = (1 << MEIXmpEventRESERVED1),         /* 0x00100000 */
MEIXmpStatusRESERVED2               = (1 << MEIXmpEventRESERVED2),         /* 0x00200000 */

MEIXmpStatusRESERVED_MASK           = (MEIXmpStatusRESERVED0 |            /* 0x00380000 */
MEIXmpStatusRESERVED1 |

```

```

MEIXmpStatusRESERVED2),

MEIXmpStatusREC_IDLE           = (1 << MEIXmpEventREC_IDLE),           /* 0x00400000 Recorder Status */
MEIXmpStatusREC_FULL           = (1 << MEIXmpEventREC_FULL),           /* 0x00800000 */
MEIXmpStatusREC_RUNNING       = (1 << MEIXmpEventREC_RUNNING),       /* 0x01000000 */
MEIXmpStatusLIMIT              = ((long)((unsigned long)1 << MEIXmpEventLIMIT)), /* 0x80000000 */

/* for backward compatibility */
MEIXmpStatusID_USER0           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER1           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER2           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER3           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER4           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER5           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER6           = MEIXmpStatusLIMIT,                   /* 0x80000000 */
MEIXmpStatusID_USER7           = MEIXmpStatusLIMIT,                   /* 0x80000000 */

MEIXmpAxisSTATUS_LATCH         = (MEIXmpStatusERROR_MASK |           /* 0x803FC010 */
MEIXmpStatusLIMIT |
MEIXmpStatusHOST |
MEIXmpStatusRESERVED_MASK |
MEIXmpStatusSTOP |
MEIXmpStatusDONE),

MEIXmpStatusMOTION             = (MEIXmpStatusDONE_MASK |           /* 0x0020001F */
MEIXmpAxisLATCH_MASK
- (MEIXmpAxisSTATE_LATCH |
- MEIXmpAxisSTATUS_LATCH);

MEIXmpStatusMOTION       = (MEIXmpStatusDONE_MASK |           /* 0x0010001D */
- (MEIXmpAxisSTATE_LATCH |
- MEIXmpAxisSTATUS_LATCH);

MEIXmpStatusIN_COARSE_POSITION |
MEIXmpStatusAT_VELOCITY |
MEIXmpStatusRESERVED2 |
MEIXmpStatusDONE),

MEIXmpMS_OR_MASK               = (MEIXmpStatusERROR_MASK |           /* 0x801FEC20 */
MEIXmpStatusLIMIT |
MEIXmpStatusHOST |
MEIXmpStatusRESERVED0 |
MEIXmpStatusRESERVED1 |
MEIXmpStatusPAUSE |
MEIXmpStatusSTOP |
MEIXmpStatusPPI |
MEIXmpStatusFRAME |
MEIXmpStatusRESET),

MEIXmpMS_AND_MASK              = MEIXmpStatusMOTION,                   /* 0x0020001F */

MEIXmpMSAxisMASK               = (MEIXmpAxisSTATUS_LATCH |           /* 0x802FE010 */
MEIXmpStatusPAUSE),

} MEIXmpStatus;

```

- **Deletion of # defines (“xmp.h” header file)**

```

/* flags used to modify state machine */
#define MEIXmpStateFlags           MEIXmpStatus

#define MEIXmpFlagDONE             MEIXmpStatusDONE
#define MEIXmpFlagRESET           MEIXmpStatusRESET
#define MEIXmpFlagSTOP            MEIXmpStatusSTOP
#define MEIXmpFlagESTOP           MEIXmpStatusESTOP
#define MEIXmpFlagESTOP_ABORT     MEIXmpStatusESTOP_ABORT
#define MEIXmpFlagABORT           MEIXmpStatusABORT

```

```

#define MEIXmpFlagERROR_MASK      MEIXmpStatusERROR_MASK
#define MEIXmpFlagHOST      MEIXmpStatusHOST

```

- **Changes to MEIXmpMotionType data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpMotionTypeINVALID          = -1,

    MEIXmpMotionTypeNONE,
MEIXmpMotionTypeUPDATE,

MEIXmpMotionTypeSTART,
MEIXmpMotionTypeMODIFY_ID,
MEIXmpMotionTypeID,

    MEIXmpMotionTypeHOLD,
    MEIXmpMotionTypeOUTPUT,
    MEIXmpMotionTypeJOG,

    MEIXmpMotionTypeVELOCITY,
    MEIXmpMotionTypeVELOCITY_JERK,
    MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypeS_CURVE_JERK,

    MEIXmpMotionTypePATH_END          = MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypePATH_OPEN,

    MEIXmpMotionTypeLAST,
    MEIXmpMotionTypeFIRST             = MEIXmpMotionTypeINVALID + 1,
} MEIXmpMotionType;

```

- **Addition of MEIXmpFrameType data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpFrameTypeINVALID          = -1,

    MEIXmpFrameTypeNONE,
    MEIXmpFrameTypeUPDATE,

    MEIXmpFrameTypeSTART,
    MEIXmpFrameTypeMODIFY_ID,
    MEIXmpFrameTypeID,

    MEIXmpFrameTypeHOLD,
    MEIXmpFrameTypeOUTPUT,

    MEIXmpFrameTypeVELOCITY,
    MEIXmpFrameTypeS_CURVE,

    MEIXmpFrameTypeLAST,
    MEIXmpFrameTypeFIRST             = MEIXmpFrameTypeINVALID + 1,
} MEIXmpFrameType;

```

- **Changes to MEIXmpFrameStatus data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpFrameStatusDIRECTION      = 0x00000001,
    MEIXmpFrameStatusTARGET         = 0x00000002,
    MEIXmpFrameStatusVELOCITY_MOVE  = 0x00010000, /* assumed S_CURVE move if not set */
}

```

```

    MEIXmpFrameStatusMOVE_IN_PROGRESS = 0x80000000,
} MEIXmpFrameStatus;

```

- **Changes to MEIXmpFrame data type (“xmp.h” header file)**

```

typedef struct MEIXmpFrame {
    MEIXmpFrameType    Type;
    float               t;
    long                Control;
    long                Position;
    float               Velocity;
    float               Accel;
    float               Jerk;
    long                Reserved;
} MEIXmpFrame;

```

- **Changes to MEIXmpStartFrame data type (“xmp.h” header file)**

```

typedef struct MEIXmpStartFrame {
    MEIXmpFrameType    Type;
    float               t;
    long                Control;
    long                Position;
    long                MoveID;
    long                ElementID;
    float               MoveTime;
    MEIXmpFrameStatus  Status;
} MEIXmpStartFrame;

```

- **Changes to MEIXmpIOFrame data type (“xmp.h” header file)**

```

typedef struct MEIXmpIOFrame {
    MEIXmpFrameType    Type;
    float               t;
    long                Control;
    long                *Ptr;
    long                Mask;
    long                Pattern;
} MEIXmpIOFrame;

```

- **Changes to MEIXmpIDFrame data type (“xmp.h” header file)**

```

typedef struct MEIXmpIDFrame {
    MEIXmpFrameType    Type;
    long                Sample;
    long                Control;
    long                Position;
    long                MoveID;
    long                ElementID;
    float               MoveTime;
    MEIXmpFrameStatus  Status;
} MEIXmpIDFrame;

```

- **Changes to MEIXmpAxis data type (“xmp.h” header file)**

```

typedef struct {
    MEIXmpLink          *Link;
    MEIXmpMotionSupervisor *MS;
    MEIXmpPosInput      APos[MEIXmpAxisPosInputs];
    long                ActualPosition;
    long                CommandPosition;
    long                TargetPosition;
    float               TargetVelocity;
    long                Origin;
}

```

```

long          Compensation;
float        ActualVelocity;
float        CommandVelocity;
float        PositionError;
float        FinePosTolerance;
long         CoarsePosTolerance;
float        VelTolerance;
long         SettlingTime;
long         SettlingCount;
MEIXmpStatus SettlingMask;
MEIXmpStatus Status;
MEIXmpStatus StateFlags;
MEIXmpState  State;
long         MoveStatus;
MEIXmpMetrics Metric;
long         ModifyIndex;
float        ModifyTime;
MEIXmpTrajectoryCalculator TC;
MEIXmpAxisGear Gear;
long         MoveID;
long         ElementID;
MEIXmpHostSignal Signal;
} MEIXmpAxis;

```

- **Addition of can.h header file** Not Supported (reserved for future use).
- **Addition of xmpcan.h header file** Not Supported (reserved for future use).
- **Deletion of eeprom.h header file**
- **Deletion of pci.h header file**
- **Deletion of pciUtil.h header file**
- **Changes to MEIMapGroup data type (“map.h” header file)**

```

typedef enum {
MEIMapGroupINVALID = -1,
MEIMapGroupMPI_ADC_CONFIG,          /* MEIMapGroupCONFIG_FIRST */
MEIMapGroupMEI_ADC_CONFIG,
MEIMapGroupMPI_AXIS_CONFIG,
MEIMapGroupMEI_AXIS_CONFIG,
MEIMapGroupMEI_CAN_CONFIG,
MEIMapGroupMPI_CAPTURE_CONFIG,
MEIMapGroupMEI_CAPTURE_CONFIG,
MEIMapGroupMPI_CONTROL_CONFIG,
MEIMapGroupMEI_CONTROL_CONFIG,
MEIMapGroupMPI_EVENTMGR_CONFIG,
MEIMapGroupMEI_EVENTMGR_CONFIG,
MEIMapGroupMPI_FILTER_CONFIG,
MEIMapGroupMEI_FILTER_CONFIG,
MEIMapGroupMPI_MOTION_CONFIG,
MEIMapGroupMEI_MOTION_CONFIG,
MEIMapGroupMPI_MOTOR_CONFIG,
MEIMapGroupMEI_MOTOR_CONFIG,
MEIMapGroupMPI_NODE_CONFIG,
MEIMapGroupMEI_NODE_CONFIG,
MEIMapGroupMPI_RECORDER_CONFIG,
MEIMapGroupMEI_RECORDER_CONFIG,
MEIMapGroupMPI_SEQUENCE_CONFIG,
MEIMapGroupMEI_SEQUENCE_CONFIG,
MEIMapGroupMPI_SERCOS_CONFIG,

```

```

MEIMapGroupMEI_SERCOS_CONFIG,          /* MEIMapGroupCONFIG_LAST */
MEIMapGroupMEI_XMP_BUFFER_DATA,       /* MEIMapGroupXMP_FIRST */
MEIMapGroupMEI_XMP_DATA,
MEIMapGroupMEI_XMP_RIPTIDE_DATA,
MEIMapGroupMEI_XMP_PLD,
MEIMapGroupMEI_XMP_SERCON,
MEIMapGroupMEI_XMP_CAN,
MEIMapGroupMEI_XMP_FRAME_BUFFER,
MEIMapGroupMEI_XMP_RECORD_BUFFER,
MEIMapGroupMEI_XMP_SERCOS_BUFFER,
                                         /* MEIMapGroupXMP_LAST */

MEIMapGroupLAST,
MEIMapGroupFIRST = MEIMapGroupINVALID + 1,

MEIMapGroupCONFIG_FIRST = MEIMapGroupMPI_ADC_CONFIG,
MEIMapGroupCONFIG_LAST= MEIMapGroupMEI_SERCOS_CONFIG + 1,

MEIMapGroupXMP_FIRST= MEIMapGroupMEI_XMP_BUFFER_DATA,
MEIMapGroupXMP_LAST= MEIMapGroupMEI_XMP_SERCON + 1
} MEIMapGroup;

```

- **Changes to MEIModuleId data type (“meidef.h” header file)**

```

typedef enum {
    MEIModuleIdPLATFORM = MPIModuleIdEXTERNAL,

    MEIModuleIdCAN,
    MEIModuleIdCLIENT,
    MEIModuleIdELEMENT,
    MEIModuleIdFLASH,
    MEIModuleIdLIST,
    MEIModuleIdMAP,
    MEIModuleIdPACKET,
    MEIModuleIdSERVER,

    MEIModuleIdLAST,
    MEIModuleIdFIRST = MPIModuleIdEXTERNAL
} MEIModuleId;

```

- **Changes to MEIPlatformBoardInfo data type (“platform.h” header file)**

```

typedef struct MEIPlatformBoardInfo {
    long    reserved;
    struct {
        long    revision;
        long    lower;
        long    upper;
    } manufacturer;
    long    serialNumber;
    long    userId;
    long    boardId;
    long    socketInfo[5];
} MEIPlatformBoardInfo;

```

- **Changes to MEIPlatformBoardInfo data type (“platform.h” header file)**

```
typedef struct MEIPlatformBoardInfo {
    long    reserved;
    struct {
        long    revision;
        long    lower;
        long    upper;
    } manufacturer;
}
```

- **Changes to # includes (“stdmei.h” header file)**

```
#include "meidef.h"

#include "can.h"
#include "client.h"
#include "element.h"
#include "firmware.h"
#include "flash.h"
#include "list.h"
#include "map.h"
#include "packet.h"
#include "platform.h"
#include "remote.h"
#include "server.h"
#include "xmpcan.h"

#if defined(__cplusplus)
extern "C" {
#endif
#endif
```

- **Changes to MEIControlVersion data type (“stdmei.h” header file)**

```
typedef struct MEIControlVersion {
    struct { /* control.c */
        char    *version;          /* MEIControlVersionMPI (YYYYMMDD) */

        struct { /* xmp.h */
            long    version; /* MEIXmpVERSION */
            long    option; /* MEIXmpOPTION */
        } firmware;
    } mpi;

    struct {
        long    version;          /* hardware version */

        struct { /* MEIXmpData.SystemData */
            long    version; /* MEIXmpVERSION_EXTRACT(SoftwareID) */
            char    revision; /* ('A' - 1) + MEIXmpREVISION_EXTRACT(SoftwareID) */
            long    subRevision; /* MEIXmpSUB_REV_EXTRACT(Option) */
            long    developmentId; /* MEIXmpDEVELOPMENT_ID_EXTRACT(Option) */
            long    option; /* MEIXmpOPTION_EXTRACT(Option) */
            long    userVersion;
            long    branchId;
        } firmware;

        struct {
            long    FPGA[MEIXmpFPGAsPerBlock];
        } motionBlock[MEIXmpMaxMotionBlocks];

        struct {
            struct {
                long    version;
            }
        }
    }
}
```



```

                long    option;
            } busInterface;
        } board[MEIXmpMaxBoards];
    } xmp;
} MEIControlVersion;

```

- **Changes to MEIControlMessage data type (“stdmei.h” header file)**

```

typedef enum {
    MEIControlMessageFIRMWARE_INVALID = MPIControlMessageLAST,
    MEIControlMessageFIRMWARE_VERSION_NONE,
    MEIControlMessageFIRMWARE_VERSION,
    MEIControlMessageSOCKETS,
    MEIControlMessageBAD_SOCKET_DATA,
    MEIControlMessageNO_SOCKET,

    MEIControlMessageLAST
} MEIControlMessage;

```

- **Addition of meiControlMemoryToFile method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlMemoryToFile(MPIControl    control,
                       char           *fileName);

```

- **Addition of meiControlSampleRate method (“stdmei.h” header file)**

```

/* Returns the controller's sampleRate */
MPI_DECL1 long MPI_DECL2
meiControlSampleRate(MPIControl    control,
                     double        *sampleRate);

```

- **Addition of meiMapFileLoadVerify method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiMapFileLoadVerify(MEIMap        map);

```

- **Deletion of MEIFilterGainStep data type (“stdmei.h” header file)**

```

typedef struct MEIFilterGainStep {
    long    stepCommand;
} MEIFilterGainStep;

```

- **Deletion of MEIFilterGainStepCoeff data type (“stdmei.h” header file)**

```

typedef enum {
    MEIFilterGainStepCoeffINVALID = -1,

    MEIFilterGainStepCoeffSTEP_COMMAND, /* Step Command */

    MEIFilterGainStepCoeffLAST,
    MEIFilterGainStepCoeffFIRST = MEIFilterGainStepCoeffINVALID + 1
} MEIFilterGainStepCoeff;

```

- **Addition of # defines (“stdmei.h” header file)**

```

/* Filter -- Postfilter */

#define MEIPi          (3.141592653589793238462643383279502884)
#define MEI2Pi        (6.283185307179586476925286766559005768)
#define MEIRoot2     (1.4142135623730950488016887242097)
#define MEIe         (2.7182818284590452353602874713527)

```

- **Addition of MEIFilterType data type (“stdmei.h” header file)**

```
typedef enum {
    MEIFilterTypeINVALID = -1,

    MEIFilterTypeUNITY_GAIN, /* B0 = 1  B1=B2=A1=A2 = 0  (effectively acting as no filter) */
    MEIFilterTypeBIQUAD,
    MEIFilterTypeSINGLE_ORDER,
    MEIFilterTypeLOW_PASS,
    MEIFilterTypeHIGH_PASS,
    MEIFilterTypeNOTCH,
    MEIFilterTypeRESONATOR,
    MEIFilterTypeLEAD_LAG,

    MEIFilterTypeZERO_GAIN, /* b0=b1=b2=a1=a2 = 0  (this does act as a filter.... zeroing the output) */

    MEIFilterTypeIIR,

    MEIFilterTypeLAST,
    MEIFilterTypeFIRST = MEIFilterTypeINVALID + 1,
} MEIFilterType;
```

- **Addition of # defines (“stdmei.h” header file)**

```
#define MEIMaxBiQuadSections  (6)
```

- **Addition of MEIPostfilterSection data type (“stdmei.h” header file)**

```
typedef struct MEIPostfilterSection {

    MEIFilterType type;

    union {

        struct {
            double breakPoint;          /* Hz */
        } lowPass;

        struct {
            double breakPoint;          /* Hz */
        } highPass;

        struct {
            double centerFrequency;     /* Hz */
            double bandwidth;           /* Hz */
        } notch;

        struct {
            double centerFrequency;     /* Hz */
            double bandwidth;           /* Hz */
            double gain;                 /* dB */
        } resonator;

        struct {
            double lowFrequencyGain;    /* dB */
            double highFrequencyGain;   /* dB */
            double centerFrequency;     /* Hz */
        } leadLag;

        /* Analog coefficients */
        struct {
```

```

        double a1;
        double a2;
        double b0;
        double b1;
        double b2;
    } biquad;

    struct {
        long numberOfCoefficients;
        double coeff[MEIXmpMAX_PostFilterSize];
    } iir;

} data;

} MEIPostfilterSection;

```

- **Addition of meiFilterPostfilterGet method (“stdmei.h” header file)**

```

/* Get all sections of a postfilter */
MPI_DECL1 long MPI_DECL2
meiFilterPostfilterGet(MPIFilter          filter,
                      long               *sectionCount,
                      MEIPostfilterSection *sections);

```

- **Addition of meiFilterPostfilterSet method (“stdmei.h” header file)**

```

/* Set multiple sections of a postfilter. Sections 0 through (numberOfSections-1) */
MPI_DECL1 long MPI_DECL2
meiFilterPostfilterSet(MPIFilter          filter,
                      long               sectionCount,
                      MEIPostfilterSection *sections);

```

- **Addition of meiFilterPostfilterSectionGet method (“stdmei.h” header file)**

```

/* Get a section of a postfilter */
MPI_DECL1 long MPI_DECL2
meiFilterPostfilterSectionGet(MPIFilter    filter,
                             long         sectionNumber,
                             MEIPostfilterSection *section);

```

- **Addition of meiFilterPostfilterSectionSet method (“stdmei.h” header file)**

```

/* Set a section of a postfilter */
MPI_DECL1 long MPI_DECL2
meiFilterPostfilterSectionSet(MPIFilter    filter,
                             long         sectionNumber,
                             MEIPostfilterSection *section);

```

- **Changes to MEIMotionMessage data type (“stdmei.h” header file)**

```

typedef enum {
    MEIMotionMessageRESERVED0 = MPIMotionMessageLAST,
    MEIMotionMessageRESERVED1,
    MEIMotionMessageRESERVED2,
    MEIMotionMessageNO_AXES_MAPPED,

    MEIMotionMessageLAST
} MEIMotionMessage;

```

- **Changes to meiMotionFrameBufferLoad method (“stdmei.h” header file)**

```
MPI_DECL1 long MPI_DECL2
meiMotionFrameBufferLoad(MPIMotionmotion,
                        long    initial,          /* TRUE/FALSE */
                        long    lock,           /* TRUE/FALSE */
                        long    frameLowEvent); /* TRUE/FALSE */
```

- **Changes to MEIMotorConfig data type (“stdmei.h” header file)**

```
typedef struct MEIMotorConfig {
    MEIMotorEncoder      Encoder[MEIXmpMotorEncoders];
    MEIXmpIO             StatusOutput[MEIXmpMotorStatusOutputs];

    MEIMotorTransceiver  Transceiver[MEIXmpMotorTransceivers];
    MEIMotorTransceiver  TransceiverExtended[MEIXmpMotorTransceiversExtended];
    long                 UserOutInvert;      /* Opto Polarity */
    MEIMotorStepper      Stepper;
    long                 EncoderTermination;
    long                 SIM4;
    MEIMotorDacConfig    Dac;

    long    pulseEnable; /* 0 => normal, else pulse output */
    long    pulseWidth;  /* 0.1 to 25.5 microseconds */

    /* Commutation is read-only from field Theta to end*/
    MEIXmpCommutationBlockCommutation;

    MEIXmpLimitDataLimit[MEIXmpLimitLAST];

    MEIXmpMotorTorqueLimitConfig TorqueLimitConfig;

    long AmpDisableWithLSR; /* TRUE => XMP disables amp when LSR is active */

    MEIMotorFilterInputFilterInput[MEIXmpMotorFilterInputs];
} MEIMotorConfig;
```

- **Deletion of MEITraceParams data type (“trace.h” header file)**

```
typedef enum {
    MEITraceParamsINVALID = -1,

    MEITraceParamsMOTION_START = -2,
    MEITraceParamsMOTION_MODIFY = -3,
    MEITraceParamsEVENT = -4,

    MEITraceParamsLAST,
    MEITraceParamsFIRST = MEITraceParamsINVALID - 1,
} MEITraceParams;
```

- **Changes to MEITraceMaskGLOBAL data type (“trace.h” header file)**

```
typedef long (*MEITraceFunction)(const char *buffer);
extern MEITraceMask
MEITraceMaskGLOBAL;
```

- **Changes to #defines (“xmp.h” header file)**

```
/* #defines and enums */

#define MEIXmpVERSION 347
/* version, 200 = 2.00 */
#define MEIXmpOPTION 0
```

```

/* FPGA Revision Number */
#define MEIXmpFPGAMBREV    241
#define MEIXmpFPGASIM4REV  211

#define MEIXmpMAXCompDimensions    (2)
#define MEIXmpCompTableSize       (512)
#define MEIXmpMAX_COORD_AXES      (16)
#define MEIXmpMAX_MESSAGES        (128)
#define MEIXmpMaxLatches          (10)
#define MEIXmpMaxComparePositions (10)

#define MEIXmpMaxRecSize           (32)
#define MEIXmpMaxCollectionSize    (8)
#define MEIXmpPointBufferSize      (MEIXmpMAX_MSs * MEIXmpMAX_Axes)
#define MEIXmpDFilterSize          (8)
#define MEIXmpMaxGainTables        (4)

```

• **Changes to MEIXmpStatus data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpStatusIN_COARSE_POSITION= (1 << MEIXmpEventIN_COARSE_POSITION), /* 0x00000001 */
    MEIXmpStatusAT_TARGET           = (1 << MEIXmpEventAT_TARGET), /* 0x00000002 */
    MEIXmpStatusAT_VELOCITY         = (1 << MEIXmpEventAT_VELOCITY), /* 0x00000004 */
    MEIXmpStatusIN_FINE_POSITION   = (1 << MEIXmpEventIN_FINE_POSITION), /* 0x00000008 */

    MEIXmpStatusSETTLED             = MEIXmpStatusIN_FINE_POSITION, /* 0x00000008 */
    MEIXmpStatusDONE_MASK          = (MEIXmpStatusSETTLED | /* 0x0000000A */
    MEIXmpStatusAT_TARGET),

    MEIXmpStatusDONE               = (1 << MEIXmpEventDONE), /* 0x00000010 */
    MEIXmpStatusIN_FINE_POSITION_LATCHED = MEIXmpStatusDONE, /* 0x00000010 */
    MEIXmpStatusPPI                 = (1 << MEIXmpEventPPI), /* 0x00000020 */
    MEIXmpStatusPS_FAULT            = (1 << MEIXmpEventPS_FAULT), /* 0x00000040 */
    MEIXmpStatusMS_FAULT           = (1 << MEIXmpEventMS_FAULT), /* 0x00000080 */
    MEIXmpStatusOUT_OF_FRAMES      = (1 << MEIXmpEventOUT_OF_FRAMES), /* 0x00000100 */
    MEIXmpStatusEXTERNAL           = (1 << MEIXmpEventEXTERNAL), /* 0x00000200 */
    MEIXmpStatusFRAME              = (1 << MEIXmpEventFRAME), /* 0x00000400 */
    MEIXmpStatusRESET              = (1 << MEIXmpEventRESET), /* 0x00000800 */

    MEIXmpStatusPAUSE              = (1 << MEIXmpEventPAUSE), /* 0x00001000 */
    MEIXmpStatusSTOP               = (1 << MEIXmpEventSTOP), /* 0x00002000 */
    MEIXmpStatusESTOP              = (1 << MEIXmpEventESTOP), /* 0x00004000 */
    MEIXmpStatusESTOP_ABORT        = (1 << MEIXmpEventESTOP_ABORT), /* 0x00008000 */
    MEIXmpStatusABORT              = (1 << MEIXmpEventABORT), /* 0x00010000 */

    MEIXmpStatusERROR_MASK         = (MEIXmpStatusESTOP | /* 0x0001C000 */
    MEIXmpStatusESTOP_ABORT |
    MEIXmpStatusABORT),

    MEIXmpStatusHOST               = (1 << MEIXmpEventHOST), /* 0x00020000 */

    MEIXmpStatusRESERVED0          = (1 << MEIXmpEventRESERVED0), /* 0x00040000 */
    MEIXmpStatusRESERVED1         = (1 << MEIXmpEventRESERVED1), /* 0x00080000 */
    MEIXmpStatusRESERVED2         = (1 << MEIXmpEventRESERVED2), /* 0x00100000 */

    MEIXmpStatusRESERVED_MASK     = (MEIXmpStatusRESERVED0 | /* 0x001C0000 */
    MEIXmpStatusRESERVED1 |
    MEIXmpStatusRESERVED2),

    MEIXmpStatusREC_IDLE          = (1 << MEIXmpEventREC_IDLE), /* 0x00200000 Recorder Status */
    MEIXmpStatusREC_FULL          = (1 << MEIXmpEventREC_FULL), /* 0x00400000 */
    MEIXmpStatusREC_RUNNING       = (1 << MEIXmpEventREC_RUNNING), /* 0x00800000 */

```

```

MEIXmpStatusLIMIT = ((long)((unsigned long)1 << MEIXmpEventLIMIT)), /* 0x80000000 */

/* for backward compatibility */
MEIXmpStatusID_USER0 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER1 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER2 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER3 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER4 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER5 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER6 = MEIXmpStatusLIMIT, /* 0x80000000 */
MEIXmpStatusID_USER7 = MEIXmpStatusLIMIT, /* 0x80000000 */

MEIXmpAxisSTATE_LATCH = (MEIXmpStatusERROR_MASK | /* 0x800FF013 */
MEIXmpStatusLIMIT |
MEIXmpStatusHOST |
MEIXmpStatusRESERVED_MASK |
MEIXmpStatusSTOP |
MEIXmpStatusAT_TARGET |
MEIXmpStatusIN_COARSE_POSITION |
MEIXmpStatusDONE),

MEIXmpAxisSTATUS_LATCH = (MEIXmpStatusERROR_MASK | /* 0x800FF013 */
MEIXmpStatusLIMIT |
MEIXmpStatusHOST |
MEIXmpStatusRESERVED_MASK |
MEIXmpStatusDONE |
MEIXmpStatusAT_TARGET |
MEIXmpStatusIN_COARSE_POSITION),

MEIXmpAxisLATCH_MASK = (MEIXmpAxisSTATE_LATCH |
MEIXmpAxisSTATUS_LATCH),

MEIXmpStatusMOTION = (MEIXmpStatusDONE_MASK | /* 0x0010001D */
MEIXmpStatusIN_COARSE_POSITION |
MEIXmpStatusAT_VELOCITY |
MEIXmpStatusRESERVED2 |
MEIXmpStatusDONE),

MEIXmpMS_OR_MASK = (MEIXmpStatusERROR_MASK | /* 0x8007FE30 */
MEIXmpStatusLIMIT |
MEIXmpStatusHOST |
MEIXmpStatusRESERVED0 |
MEIXmpStatusRESERVED1 |
MEIXmpStatusPAUSE |
MEIXmpStatusSTOP |
MEIXmpStatusPPI |
MEIXmpStatusFRAME |
MEIXmpStatusRESET),

MEIXmpMS_AND_MASK = MEIXmpStatusMOTION,

MEIXmpMSAxisMASK = (MEIXmpAxisSTATE_LATCH |
MEIXmpAxisSTATUS_LATCH |
MEIXmpStatusPAUSE), /* 0x800FF810 */
} MEIXmpStatus;

```

- **Addition of # defines (“xmp.h” header file)**

```

/* flags used to modify state machine */
#define MEIXmpStateFlags          MEIXmpStatus

#define MEIXmpFlagDONE           MEIXmpStatusDONE
#define MEIXmpFlagRESET         MEIXmpStatusRESET
#define MEIXmpFlagSTOP          MEIXmpStatusSTOP
#define MEIXmpFlagESTOP         MEIXmpStatusESTOP
#define MEIXmpFlagESTOP_ABORT   MEIXmpStatusESTOP_ABORT
#define MEIXmpFlagABORT         MEIXmpStatusABORT
#define MEIXmpFlagERROR_MASK    MEIXmpStatusERROR_MASK
#define MEIXmpFlagHOST          MEIXmpStatusHOST

```

- **Changes to MEIXmpMotionType data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpMotionTypeINVALID      = -1,

    MEIXmpMotionTypeNONE,
    MEIXmpMotionTypeUPDATE,

    MEIXmpMotionTypeSTART,
    MEIXmpMotionTypeMODIFY_ID,
    MEIXmpMotionTypeID,

    MEIXmpMotionTypeHOLD,
    MEIXmpMotionTypeOUTPUT,
    MEIXmpMotionTypeJOG,

    MEIXmpMotionTypeVELOCITY,
    MEIXmpMotionTypeVELOCITY_JERK,
    MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypeS_CURVE_JERK,

    MEIXmpMotionTypePATH_END     = MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypePATH_OPEN,

    MEIXmpMotionTypeLAST,
    MEIXmpMotionTypeFIRST       = MEIXmpMotionTypeINVALID + 1,
} MEIXmpMotionType;

```

- **Changes to MEIXmpMotionType data type (“xmp.h” header file)**

```

typedef union {
    float          f[MEIXmpFilterDataSize];
    struct {
        /* ErrorSum needs to be in the same position as PIV.PosErrorSum for Reset Integrator function to work */
        float      ErrorSum;
        float      ErrorDelta;
        float      OldError;
        float      OldVelocity;
        /* fft variables need to be in same position in both PID and PIV structures for system analysis tools to work */
        float      fftCh1;
        float      fftCh2;
        float      fftCh3;
        float      PIDOutput;
        float      DerivFilter[MEIXmpDFilterSize];
    } PID;
    struct {
        /* PosErrorSum needs to be in the same position as PID.ErrorSum for Reset Integrator function to work */
        float      PosErrorSum;
        float      VelErrorSum;
        float      OldVelocity;
    }
}

```

```

        float          OldY;
        /* fft variables need to be in same position in both PID and PIV structures for system analysis tools to work */
        float          fftCh1;
        float          fftCh2;
        float          fftCh3;
        float          PIVOutput;
    } PIV;
    struct {
        long          FF;
        float         OldVelocity;
    } SERCOS_DRIVE;
} MEIXmpFilterData;

```

- **Changes to MEIXmpAxis data type (“xmp.h” header file)**

```

typedef struct {
    MEIXmpLink          *Link;
    MEIXmpMotionSupervisor *MS;
    MEIXmpPosInput      APos[MEIXmpAxisPosInputs];
    long                ActualPosition;
    long                CommandPosition;
    long                TargetPosition;
    float               TargetVelocity;
    long                Origin;
    long                Compensation;
    float               ActualVelocity;
    float               CommandVelocity;
    float               PositionError;
    float               FinePosTolerance;
    long                CoarsePosTolerance;
    float               VelTolerance;
    long                SettlingTime;
    long                SettlingCount;
    MEIXmpStatus        SettlingMask;
    MEIXmpStatus        Status;
    MEIXmpStatus        StateFlags;
    MEIXmpState         State;
    long                TargetValid;
    MEIXmpMetrics        Metric;
    long                ModifyIndex;
    float               ModifyTime;
    MEIXmpTrajectoryCalculator TC;
    MEIXmpAxisGear       Gear;
    long                MoveID;
    long                ElementID;
    MEIXmpHostSignal     Signal;
} MEIXmpAxis;

```

- **Changes to MEIXmpServiceCmdMotor data type (“xmp.h” header file)**

```

typedef struct {
    MEIXmpServiceCmd    Config;
    MEIXmpServiceCmd    StepConfig0;
    MEIXmpServiceCmd    StepConfig1;
    MEIXmpServiceCmd    OutputA[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputB[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputC[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputD[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputE[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputF[MEIXmpLookupCmds];
    MEIXmpServiceCmd    OutputAMP_EN[MEIXmpLookupCmds];
}

```



```

MEIXmpServiceCmd      UserOut[MEIXmpLookupCmds];
MEIXmpServiceCmd      Event[MEIXmpLookupCmds];
MEIXmpServiceCmd      Compare[MEIXmpLookupCmds];
MEIXmpServiceCmd      AbsSource[MEIXmpLookupCmds];
MEIXmpServiceCmd      AbsConfig;
MEIXmpServiceCmd      SIM4Config;      /* in CAPTURE_MODE */
MEIXmpServiceCmd      Clear;
MEIXmpServiceCmd      PulseWidth;
MEIXmpServiceCmd      Clear;          /* Must be last in ServiceCmdMotor structure */
} MEIXmpServiceCmdMotor;

```

- **Changes to MEIXmpSoftware data type (“xmp.h” header file)**

```

typedef struct {
    long    ID;
    long    BranchID;
    long    Option;
    long    UserVersion;
} MEIXmpSoftware;

```

- **Addition of MEIFlashSection data type (“flash.h” header file)**

```

typedef struct MEIFlashSection {
    unsigned char    *address;
    long             size;
    long             sectorIndex;
} MEIFlashSection;

```

- **Change to MEIFlashConfig data type (“flash.h” header file)**

```

typedef struct MEIFlashConfig {
    long                wordSize;
    unsigned char       *address;
    long                size;
    unsigned char       *addressCode;
    long                sizeCode;
    unsigned char       *addressData;
    long                sizeData;
    unsigned char       *addressExternal;
    long                sizeExternal;
    long                sectorSize;
    long                sectorSize;
    MEIFlashSectionall;
    MEIFlashSectioncode;
    MEIFlashSectiondata;
    MEIFlashSectiondataExt;
    MEIFlashSectionFPGA0;
    MEIFlashSectionFPGA1;
    MEIFlashSectionFPGA2;
} MEIFlashConfig;

```

- **Addition of MEIFlashFileType data type (“flash.h” header file)**

```
typedef enum {
    MEIFlashFileTypeNONE = 0,
    MEIFlashFileTypeCode,
    MEIFlashFileTypeDataInt,
    MEIFlashFileTypeDataExt,
    MEIFlashFileTypeCodeAndData,
    MEIFlashFileTypeFPGA0,
    MEIFlashFileTypeFPGA1,
    MEIFlashFileTypeFPGA2,
    MEIFlashFileTypeALL /* Loads Code and all FPGAs (for .bin files that include the FPGA images) */
} MEIFlashFileType;
```

- **Change to MEIFlashMessage data type (“flash.h” header file)**

```
typedef enum {
    MEIFlashMessageFIRST = mpiMessageID(MEIModuleIdFLASH, 0),

    MEIFlashMessageFLASH_INVALID,
    MEIFlashMessageFLASH_READ_ERROR,
    MEIFlashMessageFLASH_WRITE_ERROR,
    MEIFlashMessagePATH,

    MEIFlashMessageLAST
} MEIFlashMessage;
```

- **Change to meiFlashMemoryFromFileType method (“flash.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    meiFlashMemoryFromFileType(MEIFlash      flash,
                               const char    *fileName,
                               MEIFlashFileType fileType);
```

- **Change to meiFlashMemoryToFile method (“flash.h” header file)**

```
PI_DECL1 long MPI_DECL2
    meiFlashMemoryToFile(MEIFlash      flash,
                        const char    *fileName,
                        MEIFlashFileType fileType);
```

- **Change to MEIMapGroup data type (“map.h” header file)**

```
typedef enum {
    MEIMapGroupINVALID = -1,

    MEIMapGroupMPI_ADC_CONFIG, /* MEIMapGroupCONFIG_FIRST */
    MEIMapGroupMEI_ADC_CONFIG,
    MEIMapGroupMPI_AXIS_CONFIG,
    MEIMapGroupMEI_AXIS_CONFIG,
    MEIMapGroupMPI_CAPTURE_CONFIG,
    MEIMapGroupMEI_CAPTURE_CONFIG,
    MEIMapGroupMPI_CONTROL_CONFIG,
    MEIMapGroupMEI_CONTROL_CONFIG,
    MEIMapGroupMPI_DAC_CONFIG,
    MEIMapGroupMEI_DAC_CONFIG,
    MEIMapGroupMPI_EVENTMGR_CONFIG,
    MEIMapGroupMEI_EVENTMGR_CONFIG,
    MEIMapGroupMPI_FILTER_CONFIG,
    MEIMapGroupMEI_FILTER_CONFIG,
    MEIMapGroupMPI_MOTION_CONFIG,
    MEIMapGroupMEI_MOTION_CONFIG,
    MEIMapGroupMPI_MOTOR_CONFIG,
```

```

MEIMapGroupMEI_MOTOR_CONFIG,
MEIMapGroupMPI_NODE_CONFIG,
MEIMapGroupMEI_NODE_CONFIG,
MEIMapGroupMPI_RECORDER_CONFIG,
MEIMapGroupMEI_RECORDER_CONFIG,
MEIMapGroupMPI_SEQUENCE_CONFIG,
MEIMapGroupMEI_SEQUENCE_CONFIG,
MEIMapGroupMPI_SERCOS_CONFIG,
MEIMapGroupMEI_SERCOS_CONFIG,
/* MEIMapGroupCONFIG_LAST */
MEIMapGroupMEI_XMP_BUFFER_DATA,
MEIMapGroupMEI_XMP_DATA,
MEIMapGroupMEI_XMP_RIPTIDE_DATA,
MEIMapGroupMEI_XMP_PLD,
MEIMapGroupMEI_XMP_SERCON,
/* MEIMapGroupXMP_FIRST */

MEIMapGroupMEI_XMP_FRAME_BUFFER,
MEIMapGroupMEI_XMP_RECORD_BUFFER,
MEIMapGroupMEI_XMP_SERCOS_BUFFER,

/* MEIMapGroupXMP_LAST */

MEIMapGroupLAST,
MEIMapGroupFIRST = MEIMapGroupINVALID + 1,

MEIMapGroupCONFIG_FIRST = MEIMapGroupMPI_ADC_CONFIG,
MEIMapGroupCONFIG_LAST = MEIMapGroupMEI_SERCOS_CONFIG + 1,

MEIMapGroupXMP_FIRST = MEIMapGroupMEI_XMP_BUFFER_DATA,
MEIMapGroupXMP_LAST = MEIMapGroupMEI_XMP_SERCON + 1
} MEIMapGroup

```

- **Addition of meiPacketClose method (“packet.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiPacketClose(MEIPacket packet);

```

- **Addition of MEIPlatformEEPromTableType data type (“platform.h” header file)**

```

#define MEIPlatformSocketInfoNA (0xFFFFFFFF)

typedef enum { /* These are 1 byte wide */
    MEIPlatformEEPromTableTypeNONE = 0x0,
    MEIPlatformEEPromTableTypeSOCKET = 0x1,
    MEIPlatformEEPromTableTypeNA = 0xFF,
} MEIPlatformEEPromTableType;

```

- **Change to MEIPlatformBoardInfo data type (“platform.h” header file)**

```

typedef struct MEIPlatformBoardInfo {
    long    boardId;
    long    userId;
    long    serialNumber;
    struct {
        long    number;
        long    revision;
    } manufacturer;
    long    reserved[2];
    long    socketInfo[5];
} MEIPlatformBoardInfo;

```

- **Change to MEIPlatformBoardType data type (“platform.h” header file)**

```
typedef enum {
    MEIPlatformBoardTypeINVALID = -1,

    MEIPlatformBoardTypeUNKNOWN,
    MEIPlatformBoardTypeHAMMERHEAD,
    MEIPlatformBoardTypeXMP,
    MEIPlatformBoardTypeXMP_EXPANSION,

    MEIPlatformBoardTypeLAST,
    MEIPlatformBoardTypeFIRST = MEIPlatformBoardTypeINVALID + 1
} MEIPlatformBoardType;
```

- **Change to meiPlatformBoardInfoGet method (“platform.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    meiPlatformBoardInfoGet(MEIPlatform          platform,
                           MEIPlatformBoardType boardType,
                           MEIPlatformBoardInfo *boardInfo);
```

- **Change to meiPlatformBoardInfoSet method (“platform.h” header file)**

```
MPI_DECL1 long MPI_DECL2
    meiPlatformBoardInfoSet(MEIPlatform          platform,
                           MEIPlatformBoardType boardType,
                           MEIPlatformBoardInfo *boardInfo);
```

- **Change to MEIRemoteMethod data type (“remote.h” header file)**

```
typedef enum {
    MEIRemoteMethodINVALID = -1,

    MEIRemoteMethodBOARD_TYPE,
    MEIRemoteMethodBOARD_INFO_GET,
    MEIRemoteMethodBOARD_INFO_SET,

    MEIRemoteMethodFLASH_MEMORY_GET,
    MEIRemoteMethodFLASH_MEMORY_SET,

    MEIRemoteMethodINTERRUPT_ENABLE,
    MEIRemoteMethodINTERRUPT_WAIT,
    MEIRemoteMethodINTERRUPT_WAKE,

    MEIRemoteMethodMEMORY,

    MEIRemoteMethodMEMORY_GET,
    MEIRemoteMethodMEMORY_SET,

    MEIRemoteMethodOBJECT_LOCK_GIVE,
    MEIRemoteMethodOBJECT_LOCK_TAKE,

    MEIRemoteMethodRESET,

    MEIRemoteMethodLAST,
    MEIRemoteMethodFIRST = MEIRemoteMethodINVALID + 1
} MEIRemoteMethod;
```

- **Addition of MEIRemoteMethodBoardInfoGet data type (“remote.h” header file)**

```
typedef struct MEIRemoteMethodBoardInfoGet {
    MEIPlatformBoardType    boardType;
    MEIPlatformBoardInfo   *boardInfo;
```

```
} MEIRemoteMethodBoardInfoGet;
```

- **Addition of MEIRemoteMethodBoardInfoSet data type (“remote.h” header file)**

```
typedef MEIRemoteMethodBoardInfoGet MEIRemoteMethodBoardInfoSet;
```

- **Change to MEIRemoteMethodArgs data type (“remote.h” header file)**

```
typedef union {  
    MEIPlatformBoardType          *boardType;  
    MEIRemoteMethodBoardInfoGet  boardInfoGet;  
    MEIRemoteMethodBoardInfoSet  boardInfoSet;  
    union {  
        long                       enable;  
        MEIRemoteMethodInterruptWait wait;  
    } interruptArgs;  
    MEIRemoteMethodMemory          memory;  
    MEIRemoteMethodMemoryGet       memoryGet;  
    MEIRemoteMethodMemorySet       memorySet;  
    MEIRemoteMethodObjectLockGive  objectLockGive;  
    MEIRemoteMethodObjectLockTake  objectLockTake;  
} MEIRemoteMethodArgs;
```

- **Change to MEIXmpRipTideTxBuff data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTideTxBuff {  
    MEIXmpRipTidePosCmd   Position[MEIXmpMaxMotionBlocks];  
    MEIXmpRipTideSample   Sample[MEIXmpMaxMotionBlocks];  
    MEIXmpRipTideCmd      Io[MEIXmpMaxMotionBlocks];  
    MEIXmpRipTideRemoraTx Remora[MEIXmpMaxSports];  
} MEIXmpRipTideTxBuff;
```

- **Addition of MEIXmpRipTideMotor data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTideMotor {  
    long   DlyCmd;  
    long   MaxInc;  
} MEIXmpRipTideMotor;
```

- **Change to MEIXmpRipTideStep data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTideStep {  
    MEIXmpRipTideMotor Motor[MEIXmpMotorsPerBlock];  
} MEIXmpRipTideStep;
```

- **Change to MEIXmpRipTidePosCmd data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTidePosCmd {  
    long           Header;  
    long           DAC[MEIXmpMotorsPerBlock];  
    MEIXmpRipTideStep Step[MEIXmpStepEnginesPerMotorBlock];  
    long           Trailer;  
} MEIXmpRipTidePosCmd;
```

- **Change to MEIXmpRipTideRxBuff data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTideRxBuff {  
    MEIXmpRipTideStatus   Io[MEIXmpMaxMotionBlocks];  
    MEIXmpRipTideRemoraRx Remora[MEIXmpMaxSports];  
    MEIXmpRipTidePosStatus Position[MEIXmpMaxMotionBlocks];  
} MEIXmpRipTideRxBuff;
```

- **Addition of MEIXmpRipTidePSIOSendWait data type (“riptide.h” header file)**

```
typedef struct MEIXmpRipTidePSIOSendWait {
    long value[MEIXmpMaxMotionBlocksPerSport];
} MEIXmpRipTidePSIOSendWait;
```

- Addition of MEIXmpRipTideSPSendWait data type (“riptide.h” header file)

```
typedef struct MEIXmpRipTideSPSendWait {
    long value[MEIXmpMaxMotionBlocksPerSport];
} MEIXmpRipTideSPSendWait;
```

- Change to MEIXMPRipTideData data type (“riptide.h” header file)

```
typedef struct MEIXmpRipTideData {
    MEIXmpRipTideTxBuff      TxBuff;
    MEIXmpRipTideRxBuff      RxBuff;
    MEIXmpRipTideTCB         TxBuffPositionTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         TxBuffSampleTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         TxBuffloTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         TxBuffRemoraTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         RxBuffloTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         RxBuffRemoraTcb[MEIXmpMaxSports];
    MEIXmpRipTideTCB         RxBuffPositionTcb[MEIXmpMaxSports];

    long      ErrorFlag;
    long      FpgaDownloadError;
long      NewWait;
long      WaitConstant;
    long      Update20khz;
    long      BlocksPerSport[MEIXmpMaxSports];
    long      NewWait[MEIXmpMaxSports];
    long      Step;
    long      CurrentWaitConstant[MEIXmpMaxSports];
    long      AvailableWaitConstant[6];
    long      AvailableSampleWait[5];
    MEIXmpRipTidePSIOSendWait AvailablePosSampleloSendWait[5];
    MEIXmpRipTideSPSendWait AvailableStepPosSendWait[5];
} MEIXmpRipTideData;
```

- **Change to MEIXMPMoveData data type (“riptide.h” header file)**

```
typedef struct MEIXmpMoveData {
    long    x0;
    float   v0;
    long    x5;
    float   v5;
    float   a[5];
    float   t[5];
    float   tmax;
    float   amax;
    float   dmax;
    float   vmax;
    float   dx;
    long    n_frames;
    long    frame_start;
    long    current_frame;
    float   new_time;
    long    origin;
    float   bl;
    MEIXmpAxis*axis;
} MEIXmpMoveData;
```

- **Addition of MEICaptureSIMConfig data type (“stdmei.h” header file)**

```
typedef struct MEICaptureSIMConfig {
    long enable;
} MEICaptureSIMConfig;
```

- **Change to MEICaptureConfig data type (“stdmei.h” header file)**

```
typedef struct MEICaptureConfig {
    MEICaptureSIMConfig SIM;
} MEICaptureConfig;
```

- **Addition of MEICompareDivideByNMode data type (“stdmei.h” header file)**

```
typedef enum {
    MEICompareDivideByNModeINVALID = -1,

    MEICompareDivideByNModeRANGE,
    MEICompareDivideByNModeFREE,

    MEICompareDivideByNModeLAST,
    MEICompareDivideByNModeFIRST = MEICompareDivideByNModeINVALID + 1
} MEICompareDivideByNMode;
```

- **Addition of MEICompareDivByNConfig data type (“stdmei.h” header file)**

```
typedef struct MEICompareDivByNConfig {
    long enable;
    long n;
} MEICompareDivByNConfig;
```

- **Change to MEICompareConfig data type (“stdmei.h” header file)**

```
typedef struct MEICompareConfig {
    long continuous;
    MEICompareDivByNConfig divByN;
} MEICompareConfig;
```

- Addition of **MEICompareDivByNParams** data type (“stdmei.h” header file)

```
typedef struct MEICompareDivByNParams {
    MPIComparestopCompare;

    double   startPosition;
    double   stopPosition;

    long     arm;
    long     dir;
    long     mode;
} MEICompareDivByNParams;
```

- Addition of **meiCompareDivideByNArm** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiCompareDivideByNArm(MPICompare           compare,
                       MEICompareDivByNParams *params);
```

- Addition of **MEIFlashFiles** data type (“stdmei.h” header file)

```
typedef struct MEIFlashFiles {
    char   binFile[MEIFlashFileMaxChars];
    char   FPGAFile[MEIXmpFlashMaxFPGAFiles][MEIFlashFileMaxChars];
} MEIFlashFiles;
```

- Addition of **meiFlashMemoryFromFile** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiFlashMemoryFromFile(MEIFlash           flash,
                       MEIFlashFiles     *filesIn,
                       MEIFlashFiles     *filesOut);
```

- Addition of **MEIControlHardwareSocketType** data type (“stdmei.h” header file)

```
typedef enum {
    MEIControlHardwareSocketTypeNONE           = 0x0,
    MEIControlHardwareSocketTypeANALOG         = 0x1,
    MEIControlHardwareSocketTypePULSE          = 0x2,
    MEIControlHardwareSocketTypeSIM4           = 0x11,
    MEIControlHardwareSocketTypeNonMBMask      = 0x10,
} MEIControlHardwareSocketType;
```

- Addition of **MEIControlHardwareICType** data type (“stdmei.h” header file)

```
typedef enum {
    MEIControlHardwareICType4044XL = 0x0,
    MEIControlHardwareICType4044XLA = 0x1,
    MEIControlHardwareICType4062XLA = 0x3,
    MEIControlHardwareICType4085XLA = 0x5,
    MEIControlHardwareICTypeASIC    = 0x7,
} MEIControlHardwareICType;
```

- Addition of **MEIControlFPGAOptionID** data type (“stdmei.h” header file)

```
typedef enum {
    MEIControlFPGAOptionID_ANALOGXL = 0x1,
    MEIControlFPGAOptionID_ANALOGXLA = 0x2,
    MEIControlFPGAOptionID_PULSEXLA = 0x3,
    MEIControlFPGAOptionID_SIM4XL    = 0x9,
    MEIControlFPGAOptionID_SIM4XLA   = 0xA,
} MEIControlFPGAOptionID;
```



- Addition of MEIControlSocketInfo data type (“stdmei.h” header file)

```
typedef struct MEIControlSocketInfo {
    long                sockets;
    MEIControlHardwareSocketType  socketType[MEIXmpMaxFPGAs];
    MEIControlHardwareICType      ICType[MEIXmpMaxFPGAs];
} MEIControlSocketInfo
```

- Addition of MEIControlRipTideConfig data type (“stdmei.h” header file)

```
typedef struct MEIControlRipTideConfig {
    long motionBlocks[MEIXmpMaxSports];
    long update20khz;
} MEIControlRipTideConfig;
```

- Addition of MEIControlFPGA data type (“stdmei.h” header file)

```
typedef struct MEIControlFPGA {
    char    FileName[MEIXmpFlashMaxFPGAFiles][MEIFlashFileMaxChars];
    long    *CodeAddress[MEIXmpMaxFPGAs];
} MEIControlFPGA;
```

- Change to MEIControlConfig data type (“stdmei.h” header file)

```
typedef struct MEIControlConfig {
    long                preFilterCount;
    long                compensatorCount;
    long                singleMotionBlock;
    MEIXmpPreFilter    PreFilter[MEIXmpMAX_PreFilters];
    MEIXmpCompensator  Compensator[MEIXmpMAX_Compensators];
    long                CompensationTable[MEIXmpCompTableSize];
    MEIXmpUserBuffer   UserBuffer;
} MEIControlConfig;
```

- Change to MEIControlVersion data type (“stdmei.h” header file)

```
typedef struct MEIControlVersion {
    struct { /* control.c */
        char    *version; /* MEIControlVersionMPI (YYYYMMDD) */

        struct { /* xmp.h */
            long    version; /* MEIXmpVERSION */
            long    option; /* MEIXmpOPTION */
        } firmware;
    } mpi;

    struct {
        long    version; /* hardware version */

        struct { /* MEIXmpData.SystemData */
            long    version; /* MEIXmpVERSION_EXTRACT(SoftwareID) */
            char    revision; /* ('A' - 1) + MEIXmpREVISION_EXTRACT(SoftwareID) */
            long    subRevision; /* MEIXmpSUB_REV_EXTRACT(Option) */
            long    developmentId; /* MEIXmpDEVELOPMENT_ID_EXTRACT(Option) */
            long    option; /* MEIXmpOPTION_EXTRACT(Option) */
        } firmware;

        struct {
            long    FPGA[MEIXmpFPGAsPerBlock];
        } motionBlock[MEIXmpMaxMotionBlocks];

        struct {
            struct {
                long    FPGA[MEIXmpFPGAsPerBlock];
                }; motionBlock[MEIXmpBlocksPerBoard];
            }
        }
    }
};
```

```

        struct {
            long    version;
            long    option;
        } busInterface;
    } board[MEIXmpMaxBoards];
} xmp;
} MEIControlVersion;

```

- **Change to MEIControlMessage data type (“stdmei.h” header file)**

```

typedef enum {
    MEIControlMessageFIRMWARE_INVALID = MPIControlMessageLAST,
    MEIControlMessageFIRMWARE_VERSION,
    MEIControlMessageSOCKETS,
    MEIControlMessageBAD_SOCKET_DATA,
    MEIControlMessageNO_SOCKET,

    MEIControlMessageLAST
} MEIControlMessage;

```

- **Addition of meiControlExtMemAvail method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlExtMemAvail(MPIControl    control,
                      long          *size);

```

- **Addition of meiControlSocketInfoGet method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlSocketInfoGet(MPIControl    control,
                        MEIControlSocketInfo *socketInfo);

```

- **Addition of meiControlSocketInfoSet method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlSocketInfoSet(MPIControl    control,
                        MEIControlSocketInfo *socketInfo);

```

- **Addition of meiControlFPGADefaultGet method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlFPGADefaultGet(MPIControl    control,
                          MEIControlSocketInfo *socketInfo,
                          MEIControlFPGA    *fpga);

```

- **Addition of meiControlFlashRipTideConfigSet method (“stdmei.h” header file)**

```

MPI_DECL1 long MPI_DECL2
meiControlFlashRipTideConfigSet(MPIControl    control,
                                MEIFlash      flash,
                                MEIControlRipTideConfig *config);

```

- **Deletion of MEIDacConfig data type (“stdmei.h” header file)**

```

typedef struct MEIDacConfig {
    float          Scale;
    MEIXmpDACInputType InputType;
    MEIXmpGenericValue Input;
};

```

- Deletion of MEIDacTrace data type (“stdmei.h” header file)

```
typedef enum {
    MEIDacTraceFIRST = MEITraceLAST << 1,

    MEIDacTraceLAST = MEIDacTraceFIRST << 16
} MEIDacTrace;
```

- Change to MEIFilterGainPIV macro (“xmp.h” header file)

```
typedef struct MEIFilterGainPIV {
    struct {
        float    proportional;    /* Kpp */
        float    integral;        /* Kip */
    } gainPosition;
    struct {
        float    proportional;    /* Kpv */
    } gainVelocity1;
    struct {
        float    position;        /* Kpff */
        float    velocity;        /* Kvff */
        float    acceleration;    /* Kaff */
        float    friction;        /* Kfff */
    } feedForward;
    struct {
        float    moving;          /* MovingIMax */
        float    rest;            /* RestIMax */
    } integrationMax;
    struct {
        float    feedback;        /* Kdv */
    } gainVelocity2;
    struct {
        float    limit;           /* OutputLimit */
        float    limitHigh;       /* OutputLimitHigh */
        float    limitLow;        /* OutputLimitLow */
        float    offset;          /* OutputOffset */
    } output;
    struct {
        float    integral;        /* Kiv */
        float    integrationMax;   /* VintMax */
    } gainVelocity3;
    struct {
        float    positionFFT;     /* Ka0 */
        float    filterFFT;       /* Ka1 */
    } noise;
} MEIFilterGainPIV;
```

- Change to MEIMotionAttrOutput data type (“stdmei.h” header file)

```
typedef struct MEIMotionAttrOutput {
    MEIMotionAttrOutputType type;
    union {
        long    *output;
        long    motor;
    } as;
    long    mask;
    long    pattern;
    long    pointIndex;          /* MEIMotionAttrMaskOUTPUT for path motion - point index for turning on output - used
                                with point lists */
} MEIMotionAttrOutput;
```

- **Change to MEIMotionAttributes data type (“stdmei.h” header file)**

```
typedef struct MEIMotionAttributes {
    MPIEventMask      eventMask; /* MEIMotionAttrMaskEVENT */
    double            *finalVelocity; /* MEIMotionAttrMaskFINAL_VEL */
    MEIMotionAttrHold *hold; /* MEIMotionAttrMaskHOLD */
    long              *outputCount; /* MEIMotionAttrMaskOUTPUT for path motion - number of outputs - per axis */
    MEIMotionAttrOutput *output; /* MEIMotionAttrMaskOUTPUT for path and non path motion - outputs - per axis */
} MEIMotionAttributes;
```

- **Change to MEIMotorMessage data type (“stdmei.h” header file)**

```
typedef enum {
    MEIMotorMessageABS_ENCODER_FAULT = MPIMotorMessageLAST,
    MEIMotorMessageABS_ENCODER_TIMEOUT,
    MEIMotorMessageMOTOR_NOT_ENABLED,

    MEIMotorMessageLAST
} MEIMotorMessage;
```

- **Addition of MEIMotorEventOpto data type (“stdmei.h” header file)**

```
/* used to define MPIMotorEventConfig.custom.io */
typedef enum {
    MEIMotorEventMaskOPTOA_IN = MEIXmpMotorIOMaskUSER,
    MEIMotorEventMaskOPTOA_OUT = MEIXmpMotorIOMaskUSER,
    MEIMotorEventMaskOPTOB_IN = MEIXmpMotorIOMaskPOS_LIMIT,
    MEIMotorEventMaskOPTOB_OUT = MEIXmpMotorIOMaskAMP_ENABLE,
    MEIMotorEventMaskOPTOC_IN = MEIXmpMotorIOMaskNEG_LIMIT,
    MEIMotorEventMaskOPTOD_IN = MEIXmpMotorIOMaskHOME,
} MEIMotorEventOpto;
```

- **Addition of MEIMotorEventMotorBlock data type (“stdmei.h” header file)**

```
/* used to define MPIMotorEventConfig.custom.motorNumber */
typedef enum {
    MEIMotorEventMotorBlockINVALID = -1,

    MEIMotorEventMotorBlock0,
    MEIMotorEventMotorBlock1,
    MEIMotorEventMotorBlock2,
    MEIMotorEventMotorBlock3,

    MEIMotorEventMotorBlockFIRST = MEIMotorEventMotorBlock0,
    MEIMotorEventMotorBlockLAST = MEIMotorEventMotorBlock3,
} MEIMotorEventMotorBlock;
```

- **Addition of meiMotorDedicatedIOAddrDecode method (“stdmei.h” header file)**

```
MPI_DECL1 long MPI_DECL2
meiMotorDedicatedIOAddrDecode(MPIMotor motor,
                               long addr,
                               long* motorNumber);
```

- **Addition of meiMotorDedicatedInAddrGet method (“stdmei.h” header file)**

```
MPI_DECL1 long MPI_DECL2
meiMotorDedicatedInAddrGet(MPIMotormotor,
                            long motorNumber);
```

- Addition of **meiMotorDedicatedOutAddrGet** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiMotorDedicatedOutAddrGet(MPIMotor    motor,
                             long        motorNumber);
```

- Change to **MEIMotorTransceiverConfig** data type (“stdmei.h” header file)

```
typedef enum {
    MEIMotorTransceiverConfigINVALID = -1,

    MEIMotorTransceiverConfigINPUT,    /* 0 */
    MEIMotorTransceiverConfigOUTPUT,   /* 1 */
    MEIMotorTransceiverConfigSTEP,     /* 2 */
    MEIMotorTransceiverConfigDIR,      /* 3 */
    MEIMotorTransceiverConfigCW,       /* 4 */
    MEIMotorTransceiverConfigCCW,      /* 5 */
    MEIMotorTransceiverConfigQUAD_A,   /* 6 */
    MEIMotorTransceiverConfigQUAD_B,   /* 7 */
    MEIMotorTransceiverConfigCOMPARE, /* 8 */
    MEIMotorTransceiverConfigDIAG,     /* 9 */
    MEIMotorTransceiverConfigNOT_AVAILABLE,

    MEIMotorTransceiverConfigLAST,
    MEIMotorTransceiverConfigFIRST = MEIMotorTransceiverConfigINVALID + 1,
} MEIMotorTransceiverConfig;
```

- Addition of **MEIMotorResourceNumber** data type (“stdmei.h” header file)

```
typedef enum {
    MEIMotorResourceNumberINVALID = -1,
    MEIMotorResourceNumber0,
    MEIMotorResourceNumber1,
    MEIMotorResourceNumber2,
    MEIMotorResourceNumber3,
    MEIMotorResourceNumber4,
    MEIMotorResourceNumber5,
    MEIMotorResourceNumber6,
    MEIMotorResourceNumber7,
    MEIMotorResourceNumber8,
    MEIMotorResourceNumber9,
    MEIMotorResourceNumber10,
    MEIMotorResourceNumber11,
    MEIMotorResourceNumber12,
    MEIMotorResourceNumber13,
    MEIMotorResourceNumber14,
    MEIMotorResourceNumber15,
    MEIMotorResourceNumber16,
    MEIMotorResourceNumber17,
    MEIMotorResourceNumber18,
    MEIMotorResourceNumber19,
    MEIMotorResourceNumber20,
    MEIMotorResourceNumber21,
    MEIMotorResourceNumber22,
    MEIMotorResourceNumber23,
    MEIMotorResourceNumber24,
    MEIMotorResourceNumber25,
    MEIMotorResourceNumber26,
    MEIMotorResourceNumber27,
    MEIMotorResourceNumber28,
    MEIMotorResourceNumber29,
    MEIMotorResourceNumber30,
    MEIMotorResourceNumber31,
```

```

MEIMotorResourceNumberLAST,
MEIMotorResourceNumberFIRST= MEIMotorResourceNumber0,
}MEIMotorResourceNumber;

```

- **Change to MEIMotorStepper data type (“stdmei.h” header file)**

```

typedef struct MEIMotorStepper {
float          PulseWidth; /* output pulse width (sec) */
long          Loopback; /* TRUE = count step pulses in encoder reg. */
MEIMotorResourceNumber ResourceNumber;
} MEIMotorStepper;

```

- **Addition of MEIMotorDacChannelConfig data type (“stdmei.h” header file)**

```

typedef struct MEIMotorDacChannelConfig {
float          Offset;          /* volts */
float          Scale;
MEIXmpDACInputType InputType;
MEIXmpGenericValue *Input;
} MEIMotorDacChannelConfig;

```

- **Addition of MEIMotorDacConfig data type (“stdmei.h” header file)**

```

typedef struct MEIMotorDacConfig {
MEIXmpDACPhase          Phase;
MEIMotorDacChannelConfig Cmd;
MEIMotorDacChannelConfig Aux;
} MEIMotorDacConfig;

```

- **Change to MEIXmpConfig data type (“stdmei.h” header file)**

```

typedef struct MEIMotorConfig {
MEIMotorEncoder          Encoder[MEIXmpMotorEncoders];
MEIXmpIO                 StatusOutput[MEIXmpMotorStatusOutputs];

MEIMotorTransceiver      Transceiver[MEIXmpMotorTransceivers];
MEIMotorTransceiver      TransceiverExtended[MEIXmpMotorTransceiversExtended];
long                     UserOutInvert; /* Opto Polarity */
MEIMotorStepper          Stepper;
long                     EncoderTermination;
long                     SIM4;
MEIMotorDacConfigDac;

long pulseEnable; /* 0 => normal, else pulse output */
long pulseWidth; /* 1 to 255 microseconds */

/* Commutation is read-only from field Theta to end*/
MEIXmpCommutationBlockCommutation;

MEIXmpLimitDataLimit[MEIXmpLimitLAST];

MEIXmpMotorTorqueLimitConfig TorqueLimitConfig;

long AmpDisableWithLSR; /* TRUE => XMP disables amp when LSR is active */

MEIMotorFilterInputFilterInput[MEIXmpMotorFilterInputs];
} MEIMotorConfig;

```

- Addition of **MEIMotorDacChannelStatus** data type (“stdmei.h” header file)

```
typedef struct MEIMotorDacChannelStatus {
    float    level;    /* volts */
} MEIMotorDacChannelStatus;
```

- Addition of **MEIMotorDacStatus** data type (“stdmei.h” header file)

```
typedef struct MEIMotorDacStatus {
    MEIMotorDacChannelStatus    cmd;
    MEIMotorDacChannelStatus    aux;
} MEIMotorDacStatus;
```

- Addition of **MEIMotorDacChannelStatus** data type (“stdmei.h” header file)

```
typedef struct MEIMotorStatus {
    MEIMotorDacStatus    dac;
} MEIMotorStatus;
```

- Addition of **meiMotorRelatedStepMotorGet** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiMotorRelatedStepMotorGet(MPIMotor    motor,
                             long        *motorNumber);
```

- Addition of **meiMotorCompareListGet** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiMotorCompareListGet(MPIMotor    motor,
                       long        *compareCount,
                       long        *compareList);
```

- Addition of **meiMotorDacConfigGet** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiMotorDacConfigGet(MPIMotor    motor,
                    MEIMotorDacConfig    *dacConfig,
                    MEIFlash        flash);
```

- Addition of **meiMotorDacConfigSet** method (“stdmei.h” header file)

```
MPI_DECL1 long MPI_DECL2
meiMotorDacConfigSet(MPIMotor    motor,
                    MEIMotorDacConfig    *dacConfig,
                    MEIFlash        flash);
```

- Addition of **MEINodeMessage** data type (“stdmei.h” header file)

```
typedef enum {
    MEINodeMessageBUFFER_SIZE_ERROR = MPINodeMessageLAST,

    MEINodeMessageLAST
} MEINodeMessage;
```

- Addition of **MEISercosMessage** data type (“stdmei.h” header file)

```
typedef enum {
    MEISercosMessageBUFFER_SIZE_ERROR = MPISercosMessageLAST,

    MEISercosMessageLAST
} MEISercosMessage;
```

- Change to **MEIXmpMotorFPGA** data type (“xmp.h” header file)

```

typedef enum {
    MEIXmpMotorFPGA_XCVR_A_OUT          = 0x00000001,
    MEIXmpMotorFPGA_XCVR_B_OUT          = 0x00000002,
    MEIXmpMotorFPGA_XCVR_C_OUT          = 0x00000004,
    MEIXmpMotorFPGA_XCVR_D_OUT          = 0x00000010,
    MEIXmpMotorFPGA_XCVR_E_OUT          = 0x00000020,
    MEIXmpMotorFPGA_XCVR_F_OUT          = 0x00000040,
    MEIXmpMotorFPGA_SIM4                 = 0x02000000,
    MEIXmpMotorFPGA_CAPMODE_SIM4        = 0x00000080,
    MEIXmpMotorFPGA_ENCODER_TERM        = 0x04000000,
    MEIXmpMotorFPGA_STEP_LOOPBACK1      = 0x08000000,
    MEIXmpMotorFPGA_STEP_LOOPBACK0      = 0x40000000,
    MEIXmpMotorFPGA_REVERSE_ENCODER     = 0x80000000,
    MEIXmpMotorFPGA_QUAD_OUT             = 0x00000001,
    MEIXmpMotorFPGA_CAPTURE_ON_CHANGE   = 0x10000000,
    MEIXmpMotorFPGA_COMPARE_CONTINUOUS = 0x00000010,
    MEIXmpMotorFPGA_PULSE_ENABLE        = 0x00000008,
} MEIXmpMotorFPGA;

```

- Change to **MEIXmpMotorLookup** data type (“xmp.h” header file)

```

typedef enum {
    /* Motor Output Configuration */
    MEIXmpMotorLookupXCVR_A0_OUT         = 0x00000010,
    MEIXmpMotorLookupXCVR_A1_OUT         = 0x00000020,
    MEIXmpMotorLookupXCVR_B0_OUT         = 0x00000010,
    MEIXmpMotorLookupXCVR_B1_OUT         = 0x00000020,
    MEIXmpMotorLookupXCVR_C_OUT         = 0x00000010,
    MEIXmpMotorLookupXCVR_D_OUT          = 0x00000010,
    MEIXmpMotorLookupXCVR_DEF_OUT        = 0x00000010,
    MEIXmpMotorLookupXCVR_E_OUT         = 0x00000010,
    MEIXmpMotorLookupXCVR_F_OUT         = 0x00000010,
    MEIXmpMotorLookupAMP_EN_OUT         = 0x00000010,

    MEIXmpMotorLookupXCVR_CASCADE       = 0x00000001,
    MEIXmpMotorLookupRESET_IN            = 0x00000001,
    MEIXmpMotorLookupDIR_IN              = 0x00000002,
    MEIXmpMotorLookupDIAG_IN             = 0x00000002,
    MEIXmpMotorLookupSTEP_IN             = 0x00000004,
    MEIXmpMotorLookupCOMPARE_INC        = 0x00000004,
    MEIXmpMotorLookupCOMPARE_IN        = 0x00000008,
    MEIXmpMotorLookupXCVR_IN             = 0x00000008,
    MEIXmpMotorLookupAMP_EN_IN          = 0x00000008,

    /* Motor UserOut Configuration */
    MEIXmpMotorLookupUSER_OUT            = 0x00000010,
    MEIXmpMotorLookupUSER_IN            = 0x00000008,
    /* Motor Event Configuration */
    MEIXmpMotorLookupCASCADE_IN          = 0x00000008,
    MEIXmpMotorLookupCASCADE_OUT         = 0x00000010,
    MEIXmpMotorLookupEVENT_OUT           = 0x00000020,
    MEIXmpMotorLookupOVERTRAVEL_POS      = 0x00000001,
    MEIXmpMotorLookupOVERTRAVEL_NEG      = 0x00000002,
    MEIXmpMotorLookupHOME                 = 0x00000004,
    MEIXmpMotorLookupINDEX                = 0x00000008,
    MEIXmpMotorLookupXCVR_A               = 0x00000001,
    MEIXmpMotorLookupXCVR_B               = 0x00000002,
    MEIXmpMotorLookupXCVR_C               = 0x00000004,
    MEIXmpMotorLookupSIM4_INDEX           = 0x00000001,
    MEIXmpMotorLookupSIM4_ENCB            = 0x00000002,
    MEIXmpMotorLookupSIM4_ENCA            = 0x00000004,
}

```



```

    MEIXmpMotorLookupSIM4_EVENT_IN      = 0x00000008,
    MEIXmpMotorLookupSIM4_EVENT_OUT    = 0x00000080,
} MEIXmpMotorLookup;

```

- **Change to MEIXmpMotionType data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpMotionTypeINVALID      = -1,

    MEIXmpMotionTypeNONE,

    MEIXmpMotionTypeSTART,
    MEIXmpMotionTypeMODIFY_ID,
    MEIXmpMotionTypeID,

    MEIXmpMotionTypeHOLD,
    MEIXmpMotionTypeOUTPUT,
    MEIXmpMotionTypeJOG,

    MEIXmpMotionTypeVELOCITY,
    MEIXmpMotionTypeVELOCITY_JERK,
    MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypeS_CURVE_JERK,

    MEIXmpMotionTypePATH_END      = MEIXmpMotionTypeS_CURVE,
    MEIXmpMotionTypePATH_OPEN,

    MEIXmpMotionTypeLAST,
    MEIXmpMotionTypeFIRST        = MEIXmpMotionTypeINVALID + 1,
} MEIXmpMotionType;

```

- **Addition of MEIXmpDACPhase data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpDACPhaseNORMAL = 0,
    MEIXmpDACPhaseINVERTED = 1,
} MEIXmpDACPhase;

```

- **Addition of MEIXmpDAC data type (“xmp.h” header file)**

```

typedef struct {
    MEIXmpDACPhase      Phase;
    MEIXmpDACChannel    Cmd;
    MEIXmpDACChannel    Aux;
} MEIXmpDAC;

```

- **Addition of MEIXmpLimitDataModifyState data type (“xmp.h” header file)**

```

typedef enum {
    MEIXmpLimitDataModifyStateIDLE = 0x0,
    MEIXmpLimitDataModifyStateMODIFY= 0x1,
    MEIXmpLimitDataModifyStateDONE = 0x2,
} MEIXmpLimitDataModifyState;

```

- Change to **MEIXmpLimitData** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpLimitCondition      Condition[MEIXmpLimitConditions];
    MEIXmpStatus              Status;
    MEIXmpLogic               Logic;
    MEIXmpLimitOutput         Output;
    /* These variables are used internally.
    They should not be changed by the Host */
    long                       Count;
    long                       State;
    MEIXmpLimitDataModifyState ModifyState;
} MEIXmpLimitData;
```

- Change to **MEIXmpPoint** data type (“xmp.h” header file)

```
typedef union {
    struct {
        long      Position;
        float     MaxVelocity;
        float     MaxAccel;
        float     MaxDecel;
        float     JerkPercent;
        float     AccelJerk;
        float     DecelJerk;
        float     EndVelocity;
        float     Delay;
        long      Control;
        long      *InPtr;
        long      InMask;
        long      InPattern;
        float     InputTimeout;
        long      *OutPtr;
        long      OutMask;
        long      OutPattern;
    } POS;
    struct {
        long      ADCCchannel;
        float     Center;
        float     Deadband;
        float     M1;
        float     M3;
    } JOG;
} MEIXmpPoint;
```

- Deletion of **MEIXmpMSAxis** data type (“xmp.h” header file)

```
typedef struct {
    long      AxisNumber;
    MEIXmpPoint Point;
} MEIXmpMSAxis;
```

- Change to **MEIXmpMSLink** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpLink      Link;
    long            DACNumber[MEIXmpCommDACs];
    long            DACs;
    MEIXmpObjectMap ADCMap;
    MEIXmpObjectMap DACMap;
    long            SercosNumber;
    long            NodeNumber;
```

- **Change to MEIXmpMSLink data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpMSAxis Axis[MEIXmpMAX_COORD_AXES];
    long Axes;
    long AxisNumber[MEIXmpMAX_COORD_AXES];
} MEIXmpMSLink
```

- **Change to MEIXmpMotorLink data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpLink Link;
    long DACNumber[MEIXmpCommDACs];
    long DACs;
    MEIXmpObjectMap ADCMap;
    MEIXmpObjectMap DACMap;
    long SercosNumber;
    long NodeNumber;
} MEIXmpMotorLink;
```

- **Change to MEIXmpMotor data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpSampleConfig SampleConfig;
    MEIXmpMotorLink *Link;
    MEIXmpMotorType Type;
    MEIXmpStatus Status;
    MEIXmpMotorIO IO;
    float CommandOutput;
    long AbortDelay;
    long AbortDelayCount;
    long EnableDelay;
    long EnableDelayCount;
    long BrakeDelay;
    long BrakeDelayCount;
    MEIXmpMotorTorqueLimitConfig TorqueLimitConfig;
    long TorqueLimitState;
    MEIXmpDAC DAC;
    MEIXmpCommutationBlock Commutation;
    MEIXmpHostSignal Signal;
} MEIXmpMotor;
```

- **Change to MEIXmpDataRecorder data type (“xmp.h” header file)**

```
typedef struct {
    long *RecAddress[MEIXmpMaxRecSize];
    long RecSize;
    long CollectionSize;
    long Period;
    long BufferLimit;
    long RecsOut;
    long RecsIn;
    long Recln;
    long Index;
    long Sample;
    long Count;
    long Enable;
    MEIXmpStatus Status;
    MEIXmpHostSignal Signal;
    long Record;
    long BufferSize;
} MEIXmpDataRecorder;
```

- Change to **MEIXmpLinkBuffer** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpDomainMap          DomainMap[MEIXmpMAX_Domains];
    MEIXmpObjectMap          ADCMap[MEIXmpMAX_ADCs];
    MEIXmpObjectMap        DACMap[MEIXmpMAX_DACs];
    MEIXmpMotorLink          MotorLink[MEIXmpMAX_Motors];
    MEIXmpLink               FilterLink[MEIXmpMAX_Filters];
    MEIXmpLink               AxisLink[MEIXmpMAX_Axes];
    MEIXmpMSLink             MSLink[MEIXmpMAX_MSs];
} MEIXmpLinkBuffer;
```

- Change to **MEIXmpServiceCmdMotor** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpServiceCmdConfig;
    MEIXmpServiceCmd          StepConfig0;
    MEIXmpServiceCmd          StepConfig1;
    MEIXmpServiceCmd          OutputA[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputB[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputC[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputD[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputE[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputF[MEIXmpLookupCmds];
    MEIXmpServiceCmd          OutputAMP_EN[MEIXmpLookupCmds];

    MEIXmpServiceCmd          UserOut[MEIXmpLookupCmds];
    MEIXmpServiceCmd          Event[MEIXmpLookupCmds];
    MEIXmpServiceCmd          Compare[MEIXmpLookupCmds];
    MEIXmpServiceCmd        Clear;
    MEIXmpServiceCmd          AbsSource[MEIXmpLookupCmds];
    MEIXmpServiceCmd          AbsConfig;
    MEIXmpServiceCmd          SIM4Config; /* in CAPTURE_MODE */
    MEIXmpServiceCmd          Clear;
    MEIXmpServiceCmd          PulseWidth;
} MEIXmpServiceCmdMotor;
```

- Change to **MEIXmpServiceCmdAux** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpServiceCmd          Config;
    MEIXmpServiceCmd        Clear;
    MEIXmpServiceCmd          AbsSource[MEIXmpLookupCmds];
    MEIXmpServiceCmd          AbsConfig;
    MEIXmpServiceCmd          Clear;
} MEIXmpServiceCmdAux;
```

- Change to **MEIXmpServiceCmdCompare** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpServiceCmd          ValueSelect[MEIXmpLookupCmds];
    MEIXmpServiceCmd          Previous[MEIXmpLookupCmds];
    MEIXmpServiceCmd          CompareMode[MEIXmpLookupCmds];
    MEIXmpServiceCmd          DivByNControl;
    MEIXmpServiceCmd          DivByNValue; /* sets "N" */
} MEIXmpServiceCmdCompare;
```

- Change to **MEIXmpServiceCmdBuffer** data type (“xmp.h” header file)

```
typedef struct {
    MEIXmpServiceCmdBlock     Block[MEIXmpMaxMotionBlocks];
} MEIXmpServiceCmdBuffer;
```

- **Change to MEIXmpBufferData data type (“xmp.h” header file)**

```
typedef struct {
    long ExtMemSize;
    MEIXmpCommandBuffer CommandBuffer;
    float CommutationTable[MEIXmpCOMM_TABLE_SIZE];
    long CompensationTable[MEIXmpCompTableSize];
    MEIXmpDomain Domain[MEIXmpMAX_Domains];
    MEIXmpLinkBuffer LinkBuffer;
    MEIXmpPoint PointBuffer[MEIXmpMAX_Axes];
    MEIXmpMessage HostMessageBuffer[MEIXmpMAX_MESSAGES];
    MEIXmpUserBuffer UserBuffer;
    MEIXmpServiceCmdBuffer ServiceCmdBuffer;
    MEIXmpSercos Sercos[MEIXmpSercosCountMAX];
    MEIXmpCaptureCompare Capture[MEIXmpMaxCaptures];
    MEIXmpCaptureCompare Compare[MEIXmpMaxCompares];
    MEIXmpMotorLimit MotorLimit[MEIXmpMAX_Motors];
    long LimitTable[MEIXmpLimitLookupSize];
    MEIXmpPreFilter PreFilter[MEIXmpMAX_PreFilters];
    MEIXmpCustomBuffer CustomBuffer;
    /* Note: Frame Buffer will not be initialized or stored in flash */
    MEIXmpFrame FrameBuffer[MEIXmpMAX_Axes * MEIXmpFrameBufferSize];
    long RecordBuffer[MEIXmpRecordBufferSize];
} MEIXmpBufferData;
```

- **Change to MEIXmpHWVersion data type (“xmp.h” header file)**

```
typedef struct {
    struct {
        long Version;
        long Option;
    } BusIF;
    long Block[MEIXmpBlocksPerBoard];
} MEIXmpHWVersion;
```

- **Addition of MEIXmpFrameBuffer data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpFrame *Ptr;
    long Size; /* number of words */
} MEIXmpFrameBuffer;
```

- **Addition of MEIXmpDataRecord data type (“xmp.h” header file)**

```
typedef struct {
    long Record;
} MEIXmpDataRecord; /* This structure needed by map module */
```

- **Addition of MEIXmpSercosBuffer data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpSercos *Ptr;
    long Size; /* number of words */
} MEIXmpSercosBuffer;
```

- **Addition of MEIXmpExtAlloc data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpFrameBuffer      FrameBuffer;      /* This should always be first in the structure so that reallocation will
                                                not require the MPI to rewrite all of the Axis' Frame pointers */

    MEIXmpDataRecordBuffer DataRecordBuffer;

    MEIXmpSercosBuffer     SercosBuffer;     /* This has a size of 0 if no Sercos hardware exists */
} MEIXmpExtAlloc;
```

- **Addition of MEIXmpSoftware data type (“xmp.h” header file)**

```
typedef struct {
    long    ID;
    long    Option;
    long    UserVersion;
} MEIXmpSoftware;
```

- **Change to MEIXmpSystemData data type (“xmp.h” header file)**

```
typedef struct {
    long    Signature;
    long    Disable;
    MEIXmpSoftware Software;
    long    SoftwareID;
    long    Option;
    long    EnabledMotors;
    long    EnabledFilters;
    long    EnabledAxes;
    long    EnabledMSs;
    long    EnabledPSs;
    long    EnabledPreFilters;
    long    EnabledCompensators;
    long    EnabledCmdDACs;
    long    EnabledAuxDACs;
    long    EnabledADCs;
    long    EnabledSercosRings;
    long    SingleMotionBlock;
    long    EnabledRecords;
    long    SamplePeriod;
    long    SampleCounter;
    long    CountDelta;
    long    BackgroundCycle;
    long    MaxForegroundTime;
    long    MaxBackgroundTime;
    long    Gate;
    long    HostGate;
    MEIXmpHWVersion HWVersion[MEIXmpMaxBoards];
    long    MotionBlockVersion[MEIXmpMaxMotionBlocks];
    long    *FPGACode[MEIXmpMaxFPGAs];
    MEIXmpExtAlloc ExtAlloc;
} MEIXmpSystemData;
```

- **Change to MEIXmpData data type (“xmp.h” header file)**

```
typedef struct {
    MEIXmpSystemData      SystemData;
    MEIXmpMotor            Motor[MEIXmpMAX_Motors];
    MEIXmpFilter           Filter[MEIXmpMAX_Filters];
    MEIXmpAxis             Axis[MEIXmpMAX_Axes];
    MEIXmpMotionSupervisor MS[MEIXmpMAX_MSs];
    MEIXmpProgramSequencer PS[MEIXmpMAX_PSs];
    MEIXmpHostMessage     HostMessage;
    MEIXmpDataRecorder    Recorder;
```

```
MEIXmpCompensator      Compensator[MEIXmpMAX_Compensators];
MEIXmpDAC            DAC[MEIXmpMAX_DACs];
MEIXmpADC              ADC[MEIXmpMAX_ADCs + 1];
MEIXmpBlock           Block[MEIXmpMaxMotionBlocks];
MEIXmpInternalData    Internal;
} MEIXmpData;
```

## 4 Motion Console and Motion Scope

### 4.1 Utilities: Closed Issues

#### 4.1.1 XMP Motion Console

Modified in Version: **03.37.19**

*Modification Type: **New Feature***

**Number**      **Name**

**839**            **[Dup. of 799] NULL firmware message**

The following error messages will now be displayed when mpiControlInit fails with the corresponding error code:

MEIControlMessageFIRMWARE\_VERSION\_NONE: No firmware is on the controller.

MEIControlMessageFIRMWARE\_VERSION: The version of firmware on the controller is invalid.

MEIControlMessageFIRMWARE\_INVALID: The firmware on the controller is invalid.

*Modification Type: **MI (Minor Improvement)***

**Number**      **Name**

**837**            **[Dup. of 810] MoCon doesn't display the state of the index input under the motor summary's bottom i/o tab**

The Index motor input bit (MEIXmpMotorIOBitINDEX) is now displayed in the Motor I/O Status tab.

*Modification Type: **Bug (PR)***

**Number**      **Name**

**834**            **Motion Console crashes when browse button in download firmware window is pressed**

If the MEI\_INSTALL\_DIR environment variable was not set, then MoCon would crash when browsing for a firmware file to upload or download.

**835**            **[Dup. of 807] Panic action does not stick**

The panic action setting was not being saved when minimizing and restoring MoCon. This has been fixed.

**836**            **[Dup. of 774] Two ampersands (&&) in a tooltip are displayed as an underline**

Two ampersands that should be displayed in a tooltip were instead being displayed as an underline.

**841**            **[Dup. of 750] Sine Comm error message limits ability to fix problem**

There is no longer a minimum number of Aux DACs required to switch to no commutation mode.

Modified in Version: **03.37.18**

*Modification Type: **DR (Discrepancy Report)***

**Number**      **Name**

**822**            **[Dup. of 821] MoCon dies when MEI\_INSTALL\_DIR does not exist**

MotionConsole uses the environment variable MEI\_INSTALL\_DIR to determine where the default .INI file is to be located. If MEI\_INSTALL\_DIR was set to a directory that didn't exist, Motion Console would crash. It now displays an appropriate error message and exits.

**823**            **[Dup. of 816] Initial directory for firmware download/upload should be MEI\_DIR**

When the user downloads or uploads firmware for the first time, the directory where the browser is set is obtained from the environment variable MEI\_DIR. There is a bug that erroneously sets this directory to C:\MEI. Since this directory normally does not exist, the initial directory for the browser is set to whatever the default .



Modified in Version:[03.37.17](#)

Modification Type:[MI \(Minor Improvement\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
788	<b>Merge Japanese Translations Intro Production Release Version</b>

Merge the current Japanese translations into the Production Release version.

Modified in Version: [03.37.16](#)

Modification Type:[MI \(Minor Improvement\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
780	<b>Display MPI Library Assertion Violations</b>

MPI library assertion violations are now displayed in a dialog box before the application exits. The user is given the choice of ignoring the error.

Modified in Version: [03.37.15](#)

Modification Type:[MI \(Minor Improvement\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
551	<b>Default firmware download directory should be ...\xmp\bin</b>

When one tries to load new firmware, the default directory should be ...\xmp\bin. Or, it should remember the last directory that was used.

Modified in Version: [03.37.14](#)

Modification Type:[MI \(Minor Improvement\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
737	<b>Make grid cell tooltips multi-line</b>

The implementation of tooltips has been modified to support multiple lines of text. If the tooltip exceeds the width of the screen, or if there are newline characters in the text, then the tooltip will be displayed with multiple lines.

Modification Type:[DR \(Discrepancy Report\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
743	<b>DAC units wrong</b>

The DAC Level units in the motor summary are in Volts. The tool tips have been modified to reflect this change.

Modified in Version:[03.37.13](#)

Modification Type:[DR \(Discrepancy Report\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
727	<b>Motion state icon changes when attribute is edited</b>

While an Axis is moving towards position 2, the right arrow state icon is displayed. Prior to this fix, if the user edited an Axis or Motion Supervisor attribute, the state icon would erroneously switch to the left arrow. The motion itself did not change, just the icon.

Modified in Version:[03.37.12](#)

Modification Type:[DR \(Discrepancy Report\)](#)

<a href="#"><u>Number</u></a>	<a href="#"><u>Name</u></a>
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**715      Downloading firmware with fewer MS objects causes library errors**

When firmware was downloaded onto a controller that resulted in there being fewer Motion Supervisors, a library error was displayed for every MS object that was no longer enabled.

**716      Modifying controller attribute while motor is in motion causes strange behavior**

If a motor was in motion and the user modified a controller attribute and then clicked on another grid, then an error message was displayed. After the message was displayed, Motion Console behaved as if the left mouse button was being held down.

**717      Object status always updated, even when not being displayed**

In general, an object status should not be updated unless it is being displayed. There was a bug that caused the object status to always be updated after the object was initially displayed.

**720      Suspect firmware files dialog box displayed at inappropriate times**

The "Suspect Firmware Files" dialog box should only be displayed when meiFlashMemoryFromFile() fails with an error code of MPIMessageFILE\_OPEN\_ERROR. It was being displayed for any error code and sometimes after downloading a good firmware file.

Modified in Version: **03.37.11**

*Modification Type:***DR (Discrepancy Report)**

<u>Number</u>	<u>Name</u>
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<b>702</b>	<b><u>Object Explorer context menus are out of sync</u></b>
------------	---

When the user right-clicked on any folder icon in the Object Explorer, an inappropriate context menu for that item was displayed.

<b>706</b>	<b><u>Controller Summary column headers should display the controller name</u></b>
------------	--

The column headers in the Controller Summary should display controller names instead of the controller index. The name is assigned to the controller when it is created by the user. The controller index is meaningless to the user and can actually conflict with the name.

<b>707</b>	<b><u>Summary profiles not saved before switching profile</u></b>
------------	---

The Summary window position and object list configuration were not being saved to the profile before switching to a different profile.

<b>708</b>	<b><u>Ctrl + S opens Save dialog box, but nothing is saved</u></b>
------------	--

Typing Ctrl + S opens a Save dialog box. The shortcut should not be defined at all.

Modified in Version: **03.37.10**

*Modification Type:***NF (New Feature)**

<u>Number</u>	<u>Name</u>
---------------	-------------

<b>690</b>	<b><u>Add a command line option to disable the splash screen</u></b>
------------	--

The option "-s X" has been added to the command line to allow the user to disable the splash screen. If the value of X is 0, then the splash screen will be disabled.

*Modification Type:***MI (Minor Improvement)**

<u>Number</u>	<u>Name</u>
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<b>692</b>	<b><u>Object Configuration Refreshed When Modified Externally</u></b>
------------	---

Motion Console will now refresh the configuration of an object immediately prior to the user editing an attribute of that object. This makes it possible for the correct configuration to be set when the configuration of an object has been modified outside of Motion Console.

*Modification Type:***CR (Change Request)**

<u>Number</u>	<u>Name</u>
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<b>687</b>	<b><u>No CellTip displayed for View I/O button when controller is uninitialized</u></b>
------------	---

The View I/O button on the Config tab page of the Controller Summary did not display a CellTip error when the controller was unable to initialize.

## Modified in Version: [03.37.08](#)

*Modification Type: [DR \(Discrepancy Report\)](#)*

### Number      Name

**585**              **Order of sub-objects can be changed when order is irrelevant**

When the Object List Configuration Dialog Box is used to modify the sub-object list of an object, the order of the sub-objects should not be modifiable if the order is irrelevant. This should be done by hiding the "Up" and "Down" buttons. This was not being done.

**597**              **Invalid object count displayed in Controller Summary window**

If an object count was changed by entering a new number and hitting <Enter> on the Config page of the Controller Summary window, and then the controller was reset, an invalid object count was being displayed when entering edit mode on the object count cell.

**658**              **Incorrect error message**

In the Motor Summary window, under the SinComm tab, attempting to modify any of the fields used to give the error message: "There is an insufficient number of DACs mapped to this motor for commutation. Make sure that there are enough DACs enabled in the controller and then map two DACs to this motor object."

Since DACs can no longer be mapped to motors, the error message has been changed to "There is an insufficient number of enabled DACs or auxiliary DACs to enable commutation for this motor. The number of DACs and auxiliary DACs enabled in the controller must be at least %d", where %d is the motor number + 1.

**683**              **Transceiver Status Reporting**

On the I/O status page of the Motor Summary, levels for transceivers D - F and and User I/O were mixed up. Transceiver D was displaying User I/O, transceiver E was displaying transceiver D, transceiver F was displaying transceiver E, and User I/O was displaying transceiver F.

## Modified in Version: [03.37.07](#)

*Modification Type: [CR \(Change Request\)](#)*

### Number              Name

**652**              **Add support for MPI version string**

The text in the "About Motion Console" dialog has been modified to correctly display the MPI version. The version of the MPI that Motion Console was compiled with has also been added.

**653**              **Ignore MPIControlMessageLIBRARY\_VERSION error from mpiControlInit()**

While the controller is being initialized, if an MPIControlMessageLIBRARY\_VERSION error occurs, then the error will be displayed, but otherwise it is ignored.

## Modified in Version: [03.37.06](#)

*Modification Type: [NF \(New Feature\)](#)*

### Number              Name

**623**              **Refresh hotkey**

The F5 key now behaves as a refresh key, as in other applications. When F5 is clicked, the display will be refreshed to reflect any changes that may have been made to the controller configuration outside of Motion Console. The behavior is exactly the same as selecting all controllers in the Object Explorer or the Controller Summary and then clicking the Refresh Display button in that window. A display refresh can also be triggered by clicking on a new icon on the main toolbar (next to the Panic Button), or by selecting the "Refresh Display" menu item under the View menu.

Modification Type: **MI (Minor Improvement)**

**Number**      **Name**

**631**            **Add shortcuts to menu items**

Many of the menu items in Motion Console have keyboard shortcuts. Unfortunately, the user must use a mouse to find out what the shortcut is. The shortcut should be added to the menu item.

Modification Type: **DR (Discrepancy Report)**

**Number**      **Name**

**639**            **Flashing Pulse Controller with MoCon doesn't work**

When downloading firmware, Motion Console was not configuring RipTide like the flash utility.

**650**            **MoCon dies when controller is deleted while being displayed in Controller Summary**

MoCon was dying when a controller was removed while being displayed in the Controller Summary.

Modified in Version: **03.37.05**

Modification Type: **NF (New Feature)**

**Number**      **Name**

**591**            **Add Splash Screen**

An MEI splash screen is now displayed as Motion Console is loading.

**649**            **Add support for new motion types: S-Curve Jerk, Velocity Jerk**

To the Axis Summary, add the following rows to the Motion tab: AccelJerk, DecelJerk. To the Motion Type combo on the MS Summary, add the following new types: S-Curve Jerk, Velocity Jerk.

Modification Type: **DR (Discrepancy Report)**

**Number**      **Name**

**632**            **Controller information not removed from .INI file after controller is removed**

After a controller has been removed, all data for that controller should be removed from the .INI file. Data for axes and motion supervisors was not being removed.

**636**            **Incorrect error message in MoCon**

When in closed loop sine comm mode, an attempt was made to change the DAC phasing, it returned an error. The message, "DAC phasing cannot be changed in open loop mode" was being displayed. The correct message should have been "... closed loop mode".

Modified in Version: **03.37.04**

Modification Type: **CR (Change Request)**

**Number**      **Name**

**638**            **New dialog box for downloading firmware**

A new dialog box for downloading firmware has been added. With the new dialog box, FPGA files can be specified as well as a .BIN file.

Modified in Version: **03.37.03**

Modification Type: **NF (New Feature)**

**Number**      **Name**

**594**            **Add Motor Stepper Configuration Attributes for XMP Pulse**

The following motor configuration attribute has been added to the Motor General Configuration tab page:  
Stepper Resource Number: MEIMotorConfig.Stepper.ResourceNumber

**595      Add new Transceiver Configuration Options for XMP Pulse**

The transceiver configuration options for transceivers A and B have been expanded to reflect the new definition of the MEIMotorTransceiverConfig enumeration.

*Modification Type:      MI (Minor Improvement)*

Number      Name

**629      Summary Tabs To Use System Menu Font**

The font used for the Summary window tabs has been changed from "Arial" to being based on the system menu font. The height of the tab beam is adjusted according to the height of the font. The system menu font is modified in the Display Properties system dialog box, under the "Appearance" tab.

*Modification Type:      DR (Discrepancy Report)*

Number      Name

**622      Japanese Font Size On All Tabs Displayed Bigger Than Expected**

Japanese fonts on the all tabs of the all summary windows were being displayed taller than the tab beam. The minor improvement implemented for issue #629 fixed this problem.

**625      ToolTips for Main Frame ToolBar Look Strange**

The ToolTips for the buttons on the Main Frame ToolBar were being displayed with a strange character in the middle of them.

**627      Clicking on another cell causes selection to change before value is set in multiple cell**

When several cells are selected, and the user modifies the value of the current cell, then the value should be set in all the cells in the selection. This wasn't happening when the user clicked on a cell that was not in the set of selected cells.

*Modification Type:      CR (Change Request)*

Number      Name

**626      Remove DAC object entirely**

The DAC object has been removed from the MPI, so it has also been removed from Motion Console. The functionality that was formerly implemented in the DAC Summary window has been moved to the Motor Summary window. The DAC configuration has been moved to the "Config" tab page and the DAC status has been moved to the "Status" tab page.

Modified in Version: **03.37.02**

*Modification Type:      MI (Minor Improvement)*

Number      Name

**607      Change Summary window style to include maximize, minimize, and restore buttons**

The maximize, minimize, and restore buttons have been reinstated to the top right corner.

**613      Move tab scroll buttons to the right of the tabs**

The tab scroll buttons have been moved to the right of the tabs. Also, the tab scroll buttons will now automatically hide when the window is large enough to display all the tabs.

**614      Add Solid Border to Top of Status Grids**

A solid border was added to the top of the status grids, just like in the configuration grids.

**615      Improved Tab Appearance**

The appearance of the tabs on the Summary windows has been made to look more tab-like.

Modification Type: **DR (Discrepancy Report)**

**Number**      **Name**

**288**            **Grid ToolTip covers up CellTip for last row**

The CellTip for the row header in the last row was obscured by the ToolTip for the grid. The ToolTip for the grid is now displayed when the user hovers over the tab for the grid. Therefore, the two ToolTips are not displayed at the same time.

**562**            **Columns disappear after resetting all columns to default width**

It is possible to get a summary window into a state where different columns are displayed in the status vs. the configuration grids. In this state, there are "hidden" columns in the configuration grid, because they are actually scrolled to the left of the grid, but there is no horizontal scrollbar allowing the user to access the hidden columns. They can be forced into the viewable area by using the arrow keys. To recreate the problem, follow these steps:

- 1) Open the axis summary window and program it to display four axes.
- 2) Select the entire grid by clicking on the top, left-most cell.
- 3) Resize all the columns by dragging right-most tracking handle.
- 4) Restore the width of every column to the default width by double-clicking on the last tracking handle.
- 5) Compare the status and configuration grids. They should be displaying the same columns.

**602**            **Tab control doesn't recognize the arrow keys**

Prior to this fix, the tab controls used in the new grid controls didn't capture the focus and didn't respond to the arrow keys. A mouse was necessary to change the tab page.

**604**            **Add Controller button on main menu bar doesn't work**

The Add Controller button on the main frame did nothing unless the Object Explorer was open and it was the active window.

**606**            **Object sub-objected lists not updated**

If Filter F is mapped to Supervisor S, then changing the mapping of motors to Filter F should automatically update the motor sub-object list for Supervisor S. This wasn't happening when the mapping was done using the Motor Map button on the Filter Summary. The problem was best demonstrated by configuring the Motor Summary to display motors for Supervisor S and then modifying the motors mapped to Filter F from the Filter Summary.

**608**            **Menus not displayed properly**

The menus at the top of the main frame were not being displayed properly.

**610**            **Wrong tab page activated when Summary is initially opened**

When a summary window is opened, its active page is restored from the .INI file. But, there was a bug that caused the active view for the window to be set to the first page. This caused all keyboard events to go to the first page, even when a different page was being displayed.

**611**            **Summary Window Doesn't Display ToolTips**

Prior to this fix, the Summary window wouldn't display ToolTips. Now, ToolTips are displayed when the user hovers over a tab or any control on a tab page. Note that a different ToolTip will be displayed for each tab that the user hovers over. Also note that a ToolTip is no longer displayed when the user hovers over the grid, as in the 03.36 series. The ToolTip that used to be displayed in this situation is now displayed when the user hovers over the active tab.

**616**            **Bottom Tab Minimized when Windows Settings Change**

When a Window's setting was changed, such as the scroll bar width, while Motion Console was running with the Motor Summary window open, the bottom part of the splitter became minimized.

**618**            **Escaping from Grid Combo List Box Causes Memory Corruption**

When the <Esc> key was pressed while a grid combo list box was dropped down, memory was being corrupted. The problem only manifested itself in the Debug version of MotionConsole.

**619**            **Drop Row and Column always set to first Cell**

When a selection of cells were dragged to another grid, the selection could only be dropped at the top, left-most cell.

**620**            **Focus not set to grid when current cell is clicked on**

If the focus was on a tab, and the user clicked on the current grid cell, then the focus would not switch to the grid. The

following procedure recreates the problem:

- 1) Open a summary window
- 2) Click on a tab
- 3) click on the grid cell located at coordinates 1, 1 (this cell is the default current cell)
- 4) note that the tab doesn't lose the focus, as indicated by the focus

**621**      **Vertical Scrollbar On Filter Coefficients Tab Page Not Calibrated Correctly**

When the Coefficients tab page on the Filter Summary window was selected the first time, the vertical ScrollBar was never calibrated such that it could be used to scroll the view.

*Modification Type:*      **CR (Change Request)**

**Number**      **Name**

**612**      **Remove the ability to edit tabs**

The feature that allowed the user to change the text displayed on the summary tabs has been removed.

Modified in Version: **03.37.00**

*Modification Type:*      **NF (New Feature)**

**Number**      **Name**

**600**      **Generalize Configuration Object/Grid**

The method used for displaying object attributes in a grid control has been generalized so that it can be used for any set of objects. The resulting Object/Grid framework can be used in other applications, such as MotionScope. It can also be used in MotionConsole to display a set of objects that are completely separate from the objects currently displayed. For example, the framework can be used to add a grid control that can be used to configure the other grid controls.

The following changes are evident to the user when compared to the previous version:

1. The title bar of the Summary windows is thinner
2. The minimize and maximize buttons and the icon have been removed from the Summary title bar
3. The tabs look different. Some aesthetic improvements can still be made to them.
4. The tab labels can be edited by double-clicking on them. The modified name is saved in the .INI file.
5. The splitter bar that divides the status and configuration tab controls can be used to resize their heights.

The changes made were sufficiently extensive to warrant stepping the minor revision number from 03.36 to 03.37. All the settings saved in the .INI file are labeled differently from those used in the 03.36 series. Therefore, when the 03.37 version is run for the first time, it will behave as if the .INI file had been removed, i.e. no controllers will be displayed in the Object Explorer. In fact, both versions of Motion Console share the same .INI file, but changes made while running one version will not affect the other version. Settings saved in the .INI file include: 1) the number of controllers and their names, 2) the position of the main window and each child window, 3) the axis trajectory values and 4) the default grid column widths.

Modified in Version: **03.36.16**

*Modification Type:*      **NF (New Feature)**

**Number**      **Name**

**596**      **Refresh related motor on Motor ConfigSet**

Modifying the configuration of a motor may cause the configuration of a related motor to also be modified. This adds the requirement that Motion Console refresh the configuration of the related motor whenever the configuration of a motor is set. The library function "meiMotorRelatedStepMotorGet()" is used to find the related motor.

Modified in Version: **03.36.14**

*Modification Type:*      **NF (New Feature)**

**Number**      **Name**

**590**            **Add support for transceivers D, E and F**

Configuration and status attributes for transceivers D, E and F has been added to the Motor I/O status and configuration pages. These transceivers are treated in the same way as transceivers A and B.



## 4.1.2 XMP Motion Scope

Modified in Version: [01.20.27](#)

Modification Type: *[Bug \(PR\)](#)*

Number    Name

**932**        **[Dup. of 931] Floating Point Data is Rounded to 3 Digits after Decimal Point**

When a pane is saved or exported, floating point data is rounded to 3 digits after the decimal point.

Modified in Version: [01.20.25](#)

Modification Type: *[DR \(Discrepancy Report\)](#)*

Number    Name

**826**        **Cannot save pane data when controller is a client type**

When the user attempts to save pane data for a pane that is connected to a client controller, nothing happens.

Modified in Version: [01.20.24](#)

Modification Type: *[DR \(Discrepancy Report\)](#)*

Number    Name

**803**        **Up the Max Motion Supervisor Number to 33**

In the Trigger dialog box, the maximum number for the Motion Supervisor has been increased from 17 to 33.  
In the Traces dialog box, the maximum "banded" axis number has been increased to 31.

Modified in Version: [01.20.23](#)

Modification Type: *[MI \(Minor Improvement\)](#)*

Number    Name

**790**        **[Dup. of 789] Merge Japanese Translations Into Production Release Version**

Merge the current Japanese translations into the Production Release version.

Modification Type: *[DR \(Discrepancy Report\)](#)*

Number    Name

**796**        **[Dup. of 262] Missing Help File**

Clicking on the menu item "Help/Help Topics" will now open an appropriate help document.

Modified in Version: [01.20.22](#)

Modification Type: *[MI \(Minor Improvement\)](#)*

Number    Name

**782**        **[Dup. of 780] Display MPI Library Assertion Violations**

MPI library assertion violations are now displayed in a dialog box before the application exits. The user is given the choice of ignoring the error.

Modified in Version: [01.20.21](#)

Modification Type: *[FE \(Future Enhancement\)](#)*

**Number      Name**

- 765      Add vertical lines to MoScope indicating when motion done, in fine position, at velocity, ... status changes**

Stock "status" Traces have been added for each MotionSupervisor in the Traces dialog for AtTarget, AtVelocity, Done, InCoarsePosition and InFinePosition. These have been set up as "binary" Traces (with values of zero or one) and are the result of masking and shifting the Status value for a given MotionSupervisor. These approximate the use of vertical lines to reflect status changes.

- 766      Increase Trace list to include 32 Axes**

Trace list has been extended to include 32 Axes.

**Modification Type: DR (Discrepancy Report)**

**Number      Name**

- 770      Cannot open .PAN file that has no data section**

When opening a .PAN file that has no data saved in it, the "Include data" checkbox is enabled only if there is a valid data header and at least one line of seemingly valid data. If the "Include data" is not checked, then the "Read Only" checkbox is cleared and disabled (as an acquire must be done to display any data). If the "Read Only" checkbox is checked, then the "Include data" checkbox is checked and disabled (as an acquire is not allowed, so the data in the file must be used).

- 771      Hex display should only be allowed for ULONG type in Edit Trace dialog.**

Hex display is only allowed for ULONG type in the Edit Trace dialog.

- 772      Trigger display cutoff when "polling" motion detection method is used.**

The beginning of the data acquire where the Trigger point would normally be displayed is no longer cutoff when the "polling" motion detection method is used.

- 773      Trigger detection by Polling fails with "Bad sample number" upon MotionStart.**

Trigger detection by the Polling method no longer fails with a "Bad sample number" message upon MotionStart.

**Modification Type: CR (Change Request)**

**Number      Name**

- 777      The default trace list to support up 32 axes (per one SynqNet controller).**

The list of axis traces has been increased to match a default of 32 in MT766.

Modified in Version:      **01.20.20**

**Modification Type: FE (Future Enhancement)**

**Number      Name**

- 459      MoScope Controller Reset**

A button has been added to the Pane Mode dialog to Reset the MPI Controller.

**Modification Type: DR (Discrepancy Report)**

**Number      Name**

- 731      Shift + LMB on Y Range Bar Slider Edge moves traces instead of scaling them**

Dragging an edge of the Range Bar with the Left Mouse Button while holding the Shift key down now rescales all the traces.

- 732      MoScope needs an IP address to "talk" to a server**

MoScope failed to initialize a controller over the network when the same controller number was used as some other Pane using a controller locally. This problem was solved by not checking the usage of controller numbers for remote/server ("Client") connections. Note that erroneous data will be reported if multiple Panes refer to the same Controller by using the server to connect to the local machine, due to the limit of one application per data Recorder and one date Recorder per Controller.

**747** **Pane with no Traces gets Config error on .INI file open.**  
A Pane with no Traces used to cause an error on .INI file open, but it is now handled correctly.

**748** **Assert occurs if YRangeBar clicked when changing focus to Pane with no Traces.**  
Assert used to occur in Debug version when YRangeBar clicked when changing focus to Pane with no Traces.

**764** **Pane draw loops when no data from triggered acquire.**  
A bug where Pane draw loops when there was no data acquired on a trigger event has been fixed.

*Modification Type:* **CR (Change Request)**

**Number**      **Name**

**744**      **Merge File Import with File Open**  
Merged File Import with File Open. Placed "Read-only" check box in File Open dialog to replace the File Import functionality. A file opened "read-only" is not attached to a controller or data source and is not allowed to perform acquires. In this manner, multiple Panes can be opened displaying previously acquired data without regard to Controller-to-Pane limitations.

**749**      **Handle drop in sample numbers from Recorder (unresolved MPI error).**  
If there is a drop in sample numbers from the Data Recorder due to any MPI errors, then an error message pops up and data acquisition is halted.

Modified in Version:      **01.20.19**

*Modification Type:*      **CR (Change Request)**

**Number**      **Name**

**728**      **Merge Pane Open/Save with File Open/Save**  
Merged Pane Open/Save with File Open/Save. Now has only one file type for settings/data files as \*.pan. Presence of data is optional in the files. Removed Pane Open/Save from the menus.

Modified in Version:      **01.20.18**

*Modification Type:* **FE (Future Enhancement)**

**Number**      **Name**

**508**      **Save trace data along with pane data**  
The ability to save the current trace data in a pane along with the pane configuration parameters has been added. Opening a pane file with trace data embedded in it with either File Open or File Import causes the data to be displayed.

*Modification Type:* **DR (Discrepancy Report)**

**Number**      **Name**

**698**      **MoScope dies when zooming in**  
After data is acquired and traces are displayed, MoScope dies when the user selects a zoom region and clicks on the Zoom In button.

**699**      **Y-Axis labels and grid lines not redrawn after data acquisition**  
After data is acquired and graphed, the Y-axis labels and grid lines disappear. They are redrawn if the window is covered up and then uncovered.

**709**      **File Import data with zero as first x point yields error.**  
File Import data with zero as first point in the first data column (X axis) is not called an error UNLESS the scaling for the X-axis is log10. In this case, zero is an illegal value.

**711**      **XRange edit box not range checking entry against MaxBuffer.**  
XRange edit box was not being range checked against MaxBuffer, causing an Assert in the Debug version and possible invalid settings in the Release version. Now, the maximum value of XRange is MaxBuffer.

**714**      **MoScope custom traces not displayed**  
For a Trace whose data value stays constant for the entire XRange of the Pane (i.e., its YRange is zero), the problem of no

data being displayed (and no YRangeBar) has been rectified. Now, for those cases where the data is a flat horizontal line, the YRange for that Trace is set arbitrarily to 10.

**Modification Type:** *CR (Change Request)*

Number                      Name

**722**                      **Rename File Import to File Import FFT**  
Renamed "File Import" to "File Import FFT" for importing FFT files.

**723**                      **Change command line parameter for FFT files.**  
Changed command line parameter to File Import FFT files from "i" to "f". "i" is used for normal File Import files.

**724**                      **Change File Open/Save functionality to include data in addition to parameters.**  
Changed File Open/Save functionality to include data in addition to parameters using the \*.mos file extension. Pane Open/Save still implements the old functionality of using settings only (and still uses the \*.pan extension).

**725**                      **File Import to read settings and data in read-only mode.**  
File Import reads settings and data in read-only mode. The same files can be used as for File Open/Save (.mos files), but the Pane will not be allowed to acquire more data from any source (other than Pane Import). This will allow multiple Panes of previously acquired data to be displayed (which had been previously restricted due to the one-Pane-per-Controller limitation).

**726**                      **Pane Import to read in data from a file in read-only mode.**  
Pane Import reads in data from a file in read-only mode (and uses the \*.txt extension). This is similar to File Import, except that Pane settings will not be changed by the file. Note that the number of Traces and Trace attributes need to match those when the data was created in order to produce meaningful results.

**Modified in Version:** **01.20.17**

**Modification Type:** *MI (Minor Improvement)*

Number                      Name

**685**                      **Use Shift Key Consistently on YRangeBar**  
The following functionality has been added to the YRangeBar:

**YRangeBar Slider:**  
Shift + Drag LMB - Move all traces

**YRangeBar Edge:**  
Shift + Drag LMB = Modify range for all traces

**YRangeBar Span:**  
Shift + Click LMB - Nudge all traces  
Ctrl + Shift + Click LMB Extend all traces

**Modification Type:** *FE (Future Enhancement)*

Number                      Name

**701**                      **Add Shift key to LMB Ctrl functions for YRangeBar.**  
To the YRangeBar the following functionality has been added:  
**Hi Span LMB Shift Ctrl:** Extend up for all Traces.  
**Li Span LMB Shift Ctrl:** Extend down for all Traces.  
**Slider LMB Shift Ctrl:** Truncate for all Traces.

**Modification Type:** *DR (Discrepancy Report)*

Number                      Name

**467** **Pane not redrawn correctly when partially covered by another window**

If a portion of a pane was covered by a window, that portion of the pane was not redrawn when the window covering it was moved to a new location. This bug is no longer reproducible.

**468** **MoScope dies after armed pane is closed**

This bug involved creating a second pane, which currently requires a second controller. This bug was reproduced by following this procedure: 1) open Motion Scope and create pane 0 and configure it to trigger on Motion Start and Buffer full; 2) create pane 1 and configure it for triggering on Motion Start and Buffer full; 3) verify that both panes trigger when motion is commanded on the appropriate Motion Supervisors; 4) save both panes to a file so that you do not have to keep recreating them after Motion Scope crashes; 5) close both panes and exit Motion Scope for a clean start; 6) restart MoScope and open the file for pane 0; 7) open the file for pane 1; 8) arm pane 0 and then close it; 9) arm pane 1 and trigger graphing on this pane by commanding motion on the Motion Supervisor associated with pane 1; 10) at this point MoScope crashed. This bug is no longer reproducible.

**496** **Trace colors are reset after Traces... dialog is run**

The trace colors were being reset after the Traces dialog was run.

**648** **MoScope crashes after a sequence of opening and importing.**

The following series of actions used to cause MoScope to crash.

1. Open a new pane and start some data acquisition on it (you'll need MoCon running, of course).
2. While the pane is still graphing, import a .fft file. When it asks to close other panes, click "yes."
3. Immediately, try importing again (without doing ANYTHING else) and pick the same .fft file. Again select "yes" when asked to close other panes. MoScope should crash. This has been rectified.

**670** **YOffset edit box not being updated via the Y-RangeBar.**

YOffset edit box was not being updated via the Y-RangeBar. This was a result of the removal of the slider controls.

**675** **File Input hangs on second invocation while closing existing Panes.**

File Input hanging on second invocation while closing existing Panes has been fixed. A race condition was eliminated.

**678** **Pane Export not supporting "hex" display format.**

Pane Export now supports "hex" display format.

**700** **Missing Trace min/max info in .INI gives Assert**

Missing Trace min/max info in .INI file (for example, if there is no .INI file) gave an unnecessary Assert in Debug version. This has been fixed.

*Modification Type: **CR (Change Request)***

Number Name

**674** **Change File Import input file Data format to not use keys per sample.**

Changed File Import input file Data format to not use keys per sample (i.e., "SAMPLE#=").

Modified in Version: **01.20.15**

*Modification Type: **NF (New Feature)***

Number Name

**592** **Add Splash Screen**

An MEI splash screen is now displayed as Motion Scope is coming up. The option "-s X" has been added to the command line to allow the user to disable the splash screen. If the value of X is 0, then the splash screen will be disabled.

**691** **Make the .INI file a command line option**

The option "-p filename" has been added to the command line to allow the user to specify an alternate .INI file. The file name can be either an absolute path, or it can be a simple file name. In the latter case, the .INI file will be created in the same directory as the default .INI file, i.e., the windows directory.

Modified in Version: **01.20.14**

*Modification Type: **MI (Minor Improvement)***

**Number**            **Name**

**572**                    **"Counts" scale on MoScope displays fixed number of scale markings, rounding each to nearest integer.**

Number of "Counts" scale markings for a Pane are no longer fixed but are now dependent on given window size and the range of counts in the Pane. Only exact labels are displayed (no rounding of labels is done).

**664**                    **Link Panes for Ctrl-LMB cursors operation.**

For Panes created via the File Import command the ability to Link Panes for Ctrl-LMB cursors operation has been added. The File Import FFT file can specify per Plot another Pane to be linked so that cross-hair cursors are displayed in the linked Pane when Ctrl-LMB is used in the first Pane. Note that the values displayed reflect those at the same relative cursor position in each Pane. This means that the values probably make the most sense when the XRange and XOffset are the same for each Pane, as well as for the Y-axis parameters. The Panes do not have to be the same exact size, as proportions are preserved in the transformation between relative positions.

**665**                    **Y-RangeBar StepIn/Out option for application to all Traces simultaneously.**

Y-RangeBar StepIn/Out option has been implemented for application to all Traces simultaneously. Applies the proportionate increase/reduction in YRange for each Trace when this option is invoked. StepInAll is invoked via LMB-Shift-DoubleClick on the Y-RangeBar slider, and StepOutAll is invoked via RMB-Shift-DoubleClick on the slider.

**666**                    **Launch MoScope with FFT file as input via command line.**

MoScope can be launched with an FFT file as input via command line. Use "-i" as the command line flag followed by the FFT import file name. Must be a legal file acceptable to the File Import menu command.

**667**                    **"Full Out" button to apply to Y-axis also.**

If Pane is created from a File Import menu command, then the "Full Out" button also applies to the Y-axis. Each Trace is restored to its original YRange and YOffset settings based upon the MinRange and MaxRange parameters specified in the file Imported.

*Modification Type: **FE (Future Enhancement)***

**Number**            **Name**

**458**                    **ZoomIn/ZoomOut with left/right mouse double click**

After selecting a ZoomIn area, it is now possible to shift-double click the left mouse button within the ZoomIn area to ZoomIn. If outside the ZoomBox or if there is no ZoomBox and the Pane has been zoomed in, the same key combination will apply ZoomOut.

*Modification Type: **DR (Discrepancy Report)***

**Number**            **Name**

**642**                    **Win98 will not import a .fft file**

Errors on File Import involving messages with "Bad or missing Data SAMPLE\_%u" have been eliminated.

**659**                    **Pane Export data not properly scaled for some Traces.**

Pane Export data is not having the internal scale factor (usually a sample rate and ms/sec conversion) applied to the ActVel, TC.Velocity and Accel Traces.

**673**                    **Ctrl-LMB on deactivated Pane leaves a little strip.**

Use of the Ctrl-LMB no longer leaves a little "strip."

*Modification Type: **CR (Change Request)***

**Number**            **Name**

**660**                    **File Import FFT files should support tab delimiters**

File Import FFT files requires tab delimiters instead of commas for separating columns of data.

Modified in Version:    **01.20.12**

*Modification Type: **MI (Minor Improvement)***

**Number**            **Name**

**453**                    **Difficult to line up cross-hairs at high magnification**

When zoomed-in at high magnification, it is now much easier to line up the cross-hairs with a desired point. The cross-hairs will snap to the nearest point.

**647**                    **The icons for new, open, & save in the toolbar have white dots in their graphic**

White dots in the graphics for the New, Open, & Save icons in the toolbar have been cosmetically removed.

**651**                    **FFT MoScope - Allow Y-RangeBar to slide (change offset) for ALL traces**

Enable all Traces to have Offset altered via the Y-RangeBar with RMB-Drag. Single (selected) Trace Offset implementation remains the same via Y-RangeBar LMB-Drag.

*Modification Type: **FE (Future Enhancement)***

**Number**            **Name**

**456**                    **StepOut with Right mouse double click**

Double clicking with the left mouse button on the RangeBar causes a "StepIn." It is now possible to "StepOut" using double clicking on the right mouse button. This has been implemented for both the X and Y-RangeBars.

**501**                    **Enforce a maximum value for MaxBuffer and Range**

A maximum value for MaxBuffer and Range is now enforced. The maximum limit for MaxBuffer is now 500,000 samples. The default values for MaxBuffer and Range are now 10,000 and 5,000 samples, respectively.

**502**                    **Print Pane feature**

The ability to print the currently active Pane has been added to MoScope via the Pane Print menu command.

**503**                    **Print Screen feature**

The ability to print the entire Motion Scope screen has been added via the File Print menu command and the Print button on the standard ToolBar.

**505**                    **Display Trace Name in ToolTip**

MoScope now displays the names of the closest Trace at a given location on a Pane when the cursor hovers near the Trace for an extended period of time.

**506**                    **Add a RangeBar for the X Axis**

A RangeBar for the Y-axis has been added, similar to the RangeBar on the X-axis.

**593**                    **Add Accel to trace list**

"Accel" has been added to the stock list of Traces.

*Modification Type: **DR (Discrepancy Report)***

**Number**            **Name**

**457**                    **RangeBar nudge size**

Left-clicking the mouse in a non-highlighted area of the RangeBar caused the XOffset value to increase arbitrarily. This increment has now been fixed to be half of the current XRange value.

**466**                    **Cannot create pane for controller when Controller # is typed**

Bug fix for the following scenario: When the user opens the Pane Mode dialog box and manually enters a number into the "Controller #" combo box (rather than selecting a number), the number is not accepted after the "OK" button is clicked. The error message "Controller not available - choose again." is displayed. This issue has now been resolved.

**497**                    **Zoombox drawn outside of pane**

Zoom boxes are now limited to be completely within the Pane area.

**498**                    **Traces with binary values drawn at edge of pane**

Traces with "binary" values are now AutoScaled better so that they are drawn within the pane, instead of at the edges.

**580**                    **MoScope crash with 28 traces**

When 28 or more traces are set, Motion Scope would crash. The number of Traces allowed has now been extended to 30,

and the user is not allowed to enter more, so MoScope no longer crashes in this scenario.

**586**                    **ToolTip for AutoScale is no longer valid**

After the new AutoScale features were added, the functionality of the AutoScale button changed, but the tooltip did not. This condition has been rectified. It now reads, "AutoScale all Traces to their current min and max values in current Range."

**587**                    **ToolTip for "Step Out" is wrong**

The tooltip for the "Step Out" button should have read "increase range," as opposed to "decrease range." This has now been rectified.

**588**                    **Holes in data when graphing continuously on Win2K**

Bug fix for the following scenario: When trigger conditions are set to "Go Button" and "Stop Button," large holes appear in the data during data acquisition. This was only noticed in Win2K (due to its slowness). This was an optimization issue and has now been resolved.

**589**                    **Y-Scale and Y-Offset not updated when new data is acquired**

After new data is acquired, the display of Y-Scale and Y-Offset did not change, even though the actual values may have been different. Selecting a new trace forced the current values of Y-Scale and Y-Offset to be displayed. This issue has now been resolved.

**633**                    **MoScope fails with 20000913 when ini file has MODE=2**

The condition where a crash occurred when the MoScope .INI file had MODE=2 is now handled gracefully.

**635**                    **Y axis scale in MoScope / trouble with small numbers**

Bug fix for the following scenario: The number spacing on the Y axis is uniform regardless of zoom rate. When the user zooms in really close, numbers are repeated ( i.e. -1,-1,-1,0,0,0,1,1,1). This issue has now been resolved.

**641**                    **MoScope crashes when trying to import .txt, .xls, or any other type of file than .fft types**

Bug fix of crash when File Import done on a file without FFT format (this is determined by the encoding within the file itself and not by the filename suffix).

**644**                    **Radio Button in MoScope gets stuck**

Bug fix for the following scenario: In the "Edit Trace Properties" Dialog box, under the "Units" category, the radio button titled "counts/sec\*\*2" gets stuck if you select it. In other words, once it's selected, you can't unselect it by selecting another radio button. Instead it actually selects both buttons. This has been resolved.

**645**                    **Strange empty window behind new pane dialog box doesn't refresh**

Bug fix for the following scenario: This works best if no other pane windows are open in MoScope. Select the "New Pane Window" icon in the toolbar and while the dialog box is open, there is an empty window behind it. What's actually strange is that the empty window does not refresh properly if you move something over it (like the dialog box) and you get a tracer effect. This has now been resolved.

**646**                    **Numbers along the x-axis overlap when they get above 100,000**

Labels on the X-Axis are no longer allowed to run into each other. This could happen previously when they were six or more digits long and the Pane was horizontally sized smaller.

*Modification Type: **CR (Change Request)***

**Number**                    **Name**

**654**                    **Ignore MPIControlMessageLIBRARY\_VERSION error from mpiControlInit()**

If, while the controller is being initialized, an MPIControlMessageLIBRARY\_VERSION error occurs, then the error will be ignored.

**655**                    **Add support for MPI version string**

The text in the "About Motion Scope" dialog has been modified to correctly display the MPI version. The version of the MPI that Motion Scope was compiled with has also been added.



Modified in Version: **01.20.08**

Modification Type: **CR (Change Report)**

**Number**      **Name**

**654**      **Ignore MPIControlMessageLIBRARY\_VERSION error from mpiControlInit()**

While the controller is being initialized, if an MPIControlMessageLIBRARY\_VERSION error occurs, then the error will be ignored.

**655**      **Add support for MPI version string**

The text in the "About Motion Scope" dialog has been modified to correctly display the MPI version. The version of the MPI that Motion Scope was compiled with has also been added.

Modification Type: **DR (Discrepancy Report)**

**Number**      **Name**

**536**      **Misleading line drawn at top and bottom of pane**

A line is drawn from the point where the value of a trace goes outside the limit of what is being graphed in the pane, and where the trace value returns to within the limit of what is being graphed. This gives the appearance that the value remains flat when in fact the value is off the graph.

**540**      **Zoom in on traces displays nothing**

When zooming in on data that crossed in and out of the zoom region many times, often nothing was being displayed. Other times only a single horizontal line was being displayed.

**577**      **ZoomBox drawn to left of Pane gets "thrown" to the right**

When the ZoomBox being drawn crossed over into the area left of the Pane, instead of truncating the ZoomBox at the left edge of the Pane, the ZoomBox was immediately mirrored to the right across the right-hand edge of itself.

**578**      **Crash upon ZoomIn when no data**

When a ZoomBox was drawn when there was no data and the ZoomIn button subsequently pushed, MoScope would crash.

**579**      **Upon startup, no Traces listed in TraceBox leading to crash upon Go**

Upon startup and loading of MoScope, the active Pane saved in the initialization file would come up with no Traces listed in the TraceList box of the PaneBar. When the Go button was pushed, a crash would occur.

## 4.2 Utilities: Open Issues

### 4.2.1 Motion Console

Issue Type: **CR (Change Request)**

<u>Number</u>	<u>Name</u>
810	Motion Console doesn't display the state of the index input under the Motor Summary's bottom i/o tab

Issue Type: **DR (Discrepancy Report)**

<u>Number</u>	<u>Name</u>
393	<b>CellTips don't work for checkboxes</b> If the text of a cell does not fit within the cell of an Object Attribute Grid, then the CellTip should display the complete text of the cell. This feature does not work for cells containing checkboxes.
427	<b>Grid Not Always Drawn Correctly When Selection Changes</b> Sometimes, selected cells are not being drawn as selected (i.e. with the colors inverted) until some window event occurs. One way to reproduce this bug is to select the entire table by clicking on the top, leftmost cell of the grid. When this is done, some cells in the grid are sometimes not drawn as inverted, but then drawn correctly when the user clicks on the grid or hovers over a control, causing a tooltip to be displayed.
561	<b>Last column cannot be sized to the edge of the grid</b> The width of the last grid column cannot be moved to the edge of the grid. If the vertical scroll bar is present, then attempting to resize the last column will cause the width to snap to a distance of 4 pixels to the left of the right edge of the grid.
564	<b>Motor Summary XCVR configuration QUADA dependence</b> When changing XCVRA or XCVRB from "QuadA" or "QuadB" to any other type of configuration, it will not allow you to do it permanently unless it is first set to "INPUT" or "OUTPUT." To repeat the problem, configure XCVRA to either QuadA or QuadB, and XCVRB to either QuadA or QuadB. Now the problem is getting out of these configurations. For example, if you attempt to change XCVRA from QuadA to Step and then leave that mini window, the window reverts back to QuadA. The only way to get out of this problem is to change QuadA to either Output or Input values. These values will remain as configurations after leaving the mini window of XCVR.
569	<b>Gray button drawn in origin cell when 1st column is minimized</b> A faulty button is drawn in the origin cell when the following procedure is followed: 1) select the entire first column of the Motion Supervisor Actions tab grid; 2) slide the column width to the narrowest possible width. This results in the gray button appearing to be a combination of all the buttons in the column.
628	<b>Horizontal Scroll Bar Behaves Strangely When Large Numbers of Objects are Displayed</b> When some summary windows are programmed to display a large number of objects (more than 20), then the scroll bar will behave strangely.
637	<b>Creative position zero behavior</b> If the controller is in open loop sine comm mode, the command position doesn't zero when the "Zero Position" button in the MS summary is clicked unless the "Clear Fault" button is clicked first.
657	<b>"(Not Available)" listed as an option in pull down menu</b> In the Motor Summary window, under the I/O configuration tab, all XCVR Config pull-down menus list "(Not Available)" as an option.
741	<b>User In bit not reported</b> The User In bit is not reported, when bit is toggled.
750	<b>Sine Comm error message limits ability to fix problem</b> When the a motor is in closed loop mode and there are not enough aux dacs turned on, an error is returned when the user tries to switch from closed loop mode to no commutation. No aux dacs should be required to switch to no commutation mode. This message should be removed in this case.

- 759**                    **CW/CCW with Invert causes Parameter invalid error**  
 Using MoCon to configure the XCVRs for CW or CCW works properly. But, selecting the inverted box causes the config word to display "?!?!?!?" and the error message "mpiMotorConfigSet: Parameter invalid" to be returned.
- This problem does not occur when using the "stepcfg.c" sample application.
- 761**                    **Pull down boxes only work on primary monitor with a multiple monitor setup on win2k**  
 When using MoCon on a Win2k system with multiple monitors, the pull down boxes don't function on the secondary monitor, but work on the primary monitor.
- 774**                    **Two ampersands (&&) in a tooltip are displayed as an underline**  
 Two ampersands that should be displayed in a tooltip are instead being displayed as an underline. Such tooltips are common on the Motor Summary window, in the Status tab page. This occurs on Win2K with IE.
- 798**                    **Block count in SynqNet Summary window refresh issue**
- 807**                    **Panic action does not stick**

Issue Type:        **MI (Minor Improvement)**

- | <b><u>Number</u></b> | <b><u>Name</u></b>  |
|----------------------|---|
| <b>739</b>           | <b>Add more detail to tooltips for disabled controller buttons</b><br>When a button on the Controller Summary is disabled because the controller is not initialized, some clues can be added to help the user rectify the situation.  |
| <b>740</b>           | <b>Add greater detail to toolbar button tooltips concerning various modes of operation</b><br>The action that is executed when a toolbar button is clicked can sometimes be modified by holding down the Ctrl or Shift keys. The nature of this modified behavior should be described in detail in the tooltip for each button. |
| <b>775</b>           | <b>Remove Broken Wire and Illegal State for Motor I/O page</b><br>Broken Wire and Illegal State statuses are displayed both in the Motor I/O and Status tab pages. They are somewhat inappropriate for the I/O window because there are no I/O pins associated with them.   |
| <b>799</b>           | <b>NULL firmware message</b>  |

## 4.2.2 Motion Scope

Issue Type: **CR (Change Request)**

<b><u>Number</u></b>	<b><u>Name</u></b>
833	More precision in Motion Scope exported floating point data

Issue Type: **DR (Discrepancy Report)**

<b><u>Number</u></b>	<b><u>Name</u></b>
542	MoScope fails to draw data on Windows 98

With triggering set to "Go Button" and "Stop Button," data will accumulate (as seen by the XOffset value changing), but no traces will be drawn. Changing the status of "View/Status Bar" will cause the pane to draw the traces. This problem occurs frequently, but irregularly. We have not found a way to reliably reproduce the problem. We have also not seen this problem on Windows NT.

**643**            **Odd behavior when opening a .pan file**

Here are the steps to reproduce the bug:

1. Open up a .pan file (previously created with File Save from MoScope).
2. Immediately hit the "Go" button.
3. While the plots are being generated, right-click somewhere on the pane and the graphing will mysteriously disappear.

Now, if you use the "Stop" button to halt data acquisition, click "Traces" to bring up the Traces list dialog and then hit the "OK" button, the problem will be solved and any graphing you do after this will not have this behavior.

**679**            **Ctrl-LMB value display hides Y-units label.**

Pane Export not supporting "hex" display format.

**713**            **MoScope Data not aligned with scale lines**

When collecting/displaying data, sometimes the data points don't align properly with the scale markers on the X axis. This is easiest to see by turning on the "sample band" in the Pane Display configuration and Displaying in Units of Samples. The problem can be corrected by forcing a re-draw of the data: sliding the data on/off the screen, minimizing/maximizing, or zooming in/out.

**769**            **MoScope hangs when opening file multiple times**

Motion Scope will sometimes hang when opening a .PAN file. This can be recreated by opening a .PAN file and then closing the pane. Repeat until the hang occurs: usually after the 4th or 5th time.

**776**            **AutoScale occasionally fails to utilize last portion of data in Range for selected Trace.**

AutoScale occasionally fails to utilize last portion of data in Range for selected Trace.

**781**            **Motion Scope displays graph as if it missed a sample when it really didn't**

While using Motion Scope to record the sample counter while I was testing motion modify code, Motion Scope displayed some data as if it missed a sample, but while investigating the sample counter I saw that this was not the case. Perhaps there is some rounding error in the calculation of elapsed time during the motion?  
The sample counter is in white. Even if MoScope missed a sample.

**802**            **The full out button should zoom to the XRange size**

**806**            **Motion Scope loses all traces after a SynqNet node disappears**

Issue Type: **MI (Minor Improvement)**

<b><u>Number</u></b>	<b><u>Name</u></b>
473	Dialog boxes missing ToolTips

None of the dialog boxes display ToolTips.

**662 Be able to parameters precision (number of digits to right of decimal point) for X and Y axis**

Add parameters that provide the ability to modify the precision (number of digits to right of decimal point) for X and Y axis data labels. Add a separate parameter for the X-axis and parameters per Trace on the Y-axis.

**663 Groups to be supported in File Import input FFT files.**

Groups to be supported in File Import input FFT files.

**818 Extend MoScope Redraw Time parameter**

## 5 MPI/MEI Libraries: Fixed Bugs

### ***mpiMotorEventConfigGet(...)* missing object locks**

**MPI 1816**

In a multithreaded application, calls to `mpiMotorEventConfigGet(...)` and `mpiMotorConfigSet(...)` from more than one thread, for the same motor object would cause incorrect "Arg Invalid" errors to be returned. The problem was caused by missing object locks in `mpiMotorEventConfigGet(...)`. This problem was fixed by adding object locks to `mpiMotorEventConfigGet(...)`.

### ***Startup script doesn't work when console cable is disconnected***

**MPI 1720**

Under some conditions, when no VxWorks console is present, applications will not execute from the startup script specified in the VxWorks boot parameters. This problem was experienced when the console cable was not attached to the eXMP-SynqNet console port. The cause was due to a bug in the MPI-VxWorks library and a bug in the standard eXMP VxWorks boot image. This problem has been fixed, but requires 1.2/1.2 version of the 5.4 VxWorks image. Please contact MEI for more information.

### ***Bug in VxWorks compiler causes positions greater than $2^{31}$ to get truncated.***

**MPI 1507**

**NOTE:** This bug only affects systems using VxWorks Version 5.4.

Positions that were greater than  $2^{31}$  were passed as doubles into the MPI. They would get truncated to 0x80000000 when cast as longs and were passed to the controller. This bug occurred when setting the origin and commanding a motion. This bug is not caused by a problem in the MPI; it is the result of a bug in the VxWorks tornado compiler. In certain cases, the compiler would truncate values when casting as a long. However, using an unsigned long cast seemed to work fine even if the result was assigned to a (signed) long variable. Changes were made to `axis.c` and `motion.c`. Casts were changed from (long) to (unsigned long) even though the variable receiving the data was a long. In the future, WindRiver might fix this problem and MEI can change the casts back to (long). See TSR # 414664 at the WindRiver support site. The cases that we identified as likely problems have been tested and fixed with the (unsigned long) cast.

### ***Changes to the Compensation Table Calculations***

**MPI 903**

Two changes were made to the compensation table calculations. The first change recast a portion of the compensation value calculation equation from a *float* to a *long*. This change was required to eliminate the immediate toggling of the compensation value on either side of a maximum compensation value in the table.

The second change removes the compensation value from the actual position that is used by the compensation table to calculate the compensation value. Now the actual position used to calculate the compensation value is calculated using only the raw encoder count and the origin. This will remove inappropriate changes in the compensation value caused by changes to the compensation value.

These two changes were made to the 371A4 firmware and the 20020117.1.5 MPI.

### ***sim4calc.exe calibration problem***

**MPI 895**

In version 20020117.1.3, `sim4calc.exe` could calculate incorrect look-up tables. This would cause incorrect interpolated position values with sinusoidal scales. The problem was caused by a rollover in the calculations to compensate for scale offsets in the look-up table. This was corrected in version 20020117.1.5.

### **Memory Access Violation with multi-point motion**

**MPI 887**

In releases 20011220.1.3 and 20020117.1.3, a bug in multi-point motion (i.e. PVT, PT, spline, etc) exists, which can cause intermittent Memory Access Violation errors. The problem was caused by an invalid pointer dereference in the frame buffer handling routines. This was corrected in version 20020117.1.5.

### **Sample Rate change causes motor faults**

**MPI 885**

In firmware version 364A3, changing sample rates could cause unexpected motor faults. This was caused by an internal timing problem between the DSP's interrupt and the serial data communication (Riptide) with local motion blocks. For a small period of time (1~2 samples), the serial data is not valid. This was corrected by waiting until the Riptide data is stable (when the sample rate is changed) before updating the background task's status. This was corrected in version 371A4.

### **Motion Supervisor 23 Initialization**

**MPI 884**

In firmware version 364A3, the internal Axis State variable for axis 23 was accidentally initialized to an incorrect value (0x1A). This caused the MPI to misinterpret the axis's state and a Stopping Error was reported. This variable has been correctly initialized to a value of 0 in version 371A2.

### **mpiFilterConfigSet(...) returns PARAM\_INVALID error**

**MPI 879**

In version 20020117.1.3, mpiFilterConfigSet(...) would improperly return a MPIMessagePARAM\_INVALID error if the Algorithm was PIV and the PostFilter.Length was non-zero. The error was caused by an internal library check to prevent the Bi-quad blocks from conflicting with the PIV algorithm. The check was not required. This has been corrected in version 20020117.1.5.

### **mpiControllnit(...) macro definition**

**MPI 843**

In previous versions, the mpiControllnit(...) macro definition had a semicolon at the end, which caused compilation errors. This typo was corrected in version 20020117.1.5.

### **meiFlashMemoryVerify(...) missing from flash.h**

**MPI 881**

In the 20000913 release, the FPGA and SHARC code was stored in a single flash image. Flash memory verification was possible using meiFlashMemoryVerify(...). In 20020117.1.3, the FPGA files were separated from the SHARC code. During flash download, the flash memory was modified to initialize an index table for the FPGA images. Thus, the meiFlashMemoryVerify(...) would fail if the entire image (code and data) was compared to a list of host files. So, the prototype was removed from flash.h. In version 20020117.1.5, the prototype was added back to flash.h. To use meiFlashMemoryVerify(...) successfully, you will need to first save the existing flash image to a file (.img) using meiFlashMemoryToFileType(..., MEIFlashFileTypeALL). Then, the flash image file can be compared to the controller's flash image using meiFlashMemoryVerify(..., MEIFlashFileTypeALL). See the sample program, checkFlash.c for more details. This error was fixed in the 20020117.1.5 release.

### **Incorrect FPGA step pulse width**

**MPI 829**

In version 242 FPGA for XMP Analog controllers, there was an improperly commented block of code, which resulted in a shortening of the step pulse by 1/4. This problem was caused by a divide-by-4 piece of logic that was removed from the pulse stretch time logic. The code was changed to reinstate the divide-by-4 logic and the problem was fixed.

### **Device Driver port call failure**

**MPI 767**

A new device driver is included in the 20020117 release to fix an existing bug (MPI723) that caused intermittent EEPROM corruption and Motion Console to crash.

This has been fixed in both WinNT and Win2000 and requires installation from the installShield release for driver replacement. To verify that the new device driver has been installed, check the date of (c:)\WinNT\System32\drivers\meixmp.sys. The date of the Win2000 driver file should be 01/21/2002. The date of the WinNT driver file should be 01/21/2002.

### ***307C2 Frame problem***

**MPI 737**

This problem was caused by incorrect handling of the UPDATE frame. This problem has only been reported in the 307 versions of the firmware. The 307D1 (307C5\_307D1 branch) version was created to correct the problem (307D3 from the 307C6\_307D2 branch, does NOT correct the problem). 310 versions of the firmware were tested and the problem did not occur.

### ***IN\_FINE\_POSITION is incorrectly calculated***

**MPI 735**

This problem was due to a change in 340A1 where the IN\_FINE criteria was only checked in the STOPPED state. This was corrected in firmware 341B3.

### ***Motion DONE occurs before State = IDLE***

**MPI 734**

Motion DONE events occur at the beginning of the execution of UPDATE frames, which can be up to 2 samples before the Motion Supervisor state becomes IDLE. This will cause mpiMotionStart() calls occurring right after a DONE event to cause a MOVING error. This problem has been corrected in the latest release.

### ***EventConfig timeout***

**MPI 691**

Under specific conditions an erroneous TIMEOUT return value was returned from mpiMotorEventConfigSet(...). This only occurred if a limit was disabled using a previous call to EventConfigSet(...) with Condition Logic set to MEIXmpLogicNEVER. The next call to mpiMotorEventConfigSet(...) would return a timeout. This bug has been corrected in the latest release.

### ***mpiMotorStatus(...) and meiMotorStatus(...) error***

**MPI 581**

In previous versions, mpiMotorStatus(...) and meiMotorStatus(...) returned MPIMessageARG\_INVALID if the external argument was not-NULL. This was corrected in version 20010125.

### ***mpiAxisCommandPositionSet(...)***

**MPI 528**

In previous versions, mpiAxisCommandPositionSet(...) would not set the command position if the axis was in a Stop condition. No error code was returned. Note, setting the command position worked after an E-Stop or Abort action. During a Stop Action, the XMP continually calculates new command positions, but uses a feedrate of 0 (this allows us to either resume the motion or back up on path). Because the XMP is calculating the command position, the MPI is not allowed to write to the command position. In version 20010710, a check was added to the MPI to verify that the command position was successfully set. If the command position cannot be set, mpiCommandPositionSet(...) will return an error code.

### ***mpiControlReset(...) returns too early***

**23**

In previous releases, mpiControlReset(...) waited a fixed time period for the controller hardware to complete its reset. Occasionally, mpiControlReset(...) would return too early, causing MPI methods to fail. mpiControlReset(...) has been changed to monitor the controller hardware during reset, returning only after the reset completion. This was corrected in MPI version 20010130.

### ***FrameBuffer referencing error***

**MPI 632**

In version 20010403, when the motion parameter point.retain is set to FALSE with mpiMotionStart(...), the internal method meiMotionFrameBufferLoad(...) deletes its frameBuffer after use. Later, when meiMotion-



FrameBufferLoad(...) is called again, the function assumes the frameBuffer is still valid, and attempts to access the members Count and Index, which results in a memory referencing error. This was corrected in version 20010807.

### **Executing flash utility with server option fails**

**MPI 625**

In version 20010403, the utility program flash.exe did not work properly with the "-server" option. This was corrected in version 20010522.

### **Reset after Stop**

**MPI 586**

In previous versions, performing a mpiMotionAction(MPIActionSTOP), polling mpiMotionStatus(...) for the axis to be IDLE, and then performing mpiMotionAction(MPIActionRESET) can cause the following error:

ERROR 0xd09: Motion: MPIStateSTOPPING

This occurred because the method mpiMotionStatus(...) reads directly from the XMP axis status. mpiMotionAction(MPIActionRESET) checks the status of the XMP motion supervisor status. The firmware updates the MS status from the Axis status in the background cycle. It takes at least one sample for the MS status to reflect the IDLE state from the Axis status. Therefore a MPIActionRESET immediately after the axis status changes to IDLE can produce MPIStateSTOPPING errors because the DSP has not yet updated the MS status. This was corrected in version 20010524.

### **mpiMotorloGet(...) and mpiMotorloSet(...) access different parts of memory**

**MPI 573**

In previous versions, if the following MPI calls are made consecutively with the same MPIMotor object as an argument, the changes made by the first call to mpiMotorloSet(...) could be erased because of Riptide latencies.

**mpiMotorloGet(...), mpiMotorloSet(...), mpiMotorloGet(...), mpiMotorloSet(...)**

These were corrected in version 20010614.

### **Action synchronization between the MPI and Firmware**

**MPI 544**

In many cases the MPI writes a value to the XMP, the XMP processes the data, calculating a new value (foreground and/or background cycle) and then the MPI reads this new value. In some specific cases, the MPI is not protected from reading the data before the XMP has completed its processing. In these cases, the MPI will read the old value. Here are the unprotected dependencies:

- 1) Motor->IO.DedicatedOUT.IO (read by mpiMotorloGet(...)) depends on Motor->IO.HostOutput (set by mpiMotorloSet(...))
- 2) SystemData->Gate (read by meiControlGateGet(...)) depends on SystemData->HostGate (set by meiControlGateSet(...))

This was corrected in version 20010614.

### **Motion supervisor pointer problem**

**MPI 516**

When changing the motion supervisor to axes mapping, the motion supervisor pointer in the axes objects continues to point to a motion supervisor after the motion supervisor stops pointing to the axis. This can cause strange behavior, such as axes that are in an error state resuming motion when another axis is set in motion. This problem only arises when an application changes the mapping of axes to motion supervisors in the middle of an application and does not reassign the old axes to new motion supervisors.

### ***Motion Modify Problem***

**MPI 769**

In version 2000072803, if mpiMotionModify(...) was called during a Stop action, it could have incorrectly returned an MPIMessageOK without having modified the move. This problem was caused by an improper error check in the mpiMotionModify(...). At the end of a Stop action, if the command velocity was zero and the Done status bit had not been set, the MPI would incorrectly consider the Stop action complete. This problem was corrected in versions 2000072804 and 20011213. Now, the mpiMotionModify(...) routine correctly checks to see if the Stop action is complete. If it is not complete, it will return a STOPPING error code.

### ***mpiRecorderRecordGet() returns corrupted data***

**MPI 713**

A recorder overflow can occur whenever the XMP fills the record buffer faster than the MPI can remove the data. Since the record buffer is circular, an overflow can cause new records to overwrite older records. In version 20000913, if the MPI read records when an overflow occurred, the data might have a mix of new and old records. The overflow recovery has been improved in version 20011213. When an overflow occurs, the MPI only reads the new records and omits the old records, preserving data integrity.

### ***Motion Modify does not work when command position is reached***

**MPI 697**

The firmware motion supervisor code would not change the command position when a call to mpiMotionModify(...) was made after the command position had reached the target position even though the motion had not been completed (met the settling criteria). This problem has been fixed in the 341B2 firmware. A call to mpiMotionModify(...) can now be made before or after the command position has reached the target position.

### ***mpiMotorConfigGet() error***

**MPI 688**

In version 20010417.1, mpiMotorConfigGet(...) would return a MEIMotorTransceiverConfigNOT\_AVAILABLE error if both the MPIMotorConfig and MEIMotorConfig structures were passed. This was caused by the MPI not reading the Stepper ResourceNumber from the controller. This bug was corrected in version 20011213.

### ***Incorrect Motion Profile with mpiMotionModify()***

**MPI 686**

In Version 325B2, if mpiMotionModify(...) was called with the same motion parameters as the executing move while moving in the negative direction, the resultant motion profile would have a discontinuity. This problem was fixed in firmware version 347B1.

### ***Motion Modification Bug for Velocity Moves***

**MPI 683**

In version 325B2, mpiMotionModify(...) would cause a trajectory discontinuity with velocity type moves. This was fixed in version 347B1.

### ***Config Utility does not save DRate coefficient***

**MPI 672**

In previous versions of the config.exe utility, the filter coefficient value for DRate was being incorrectly saved. Upgrading XMP configurations using a config utility output file from a previous version will restore incorrect values for DRate. MEI suggests setting the configuration using the config utility and then manually modifying the DRate in Motion Console. This suggestion only applies to customers using the PID control algorithm and the config.exe utility for XMP configuration. This discrepancy has been resolved in the 20011213 release.

### ***mpiControlReset(...) locks up PCI bus*** **MPI 659**

In firmware version 310B (and older), under certain, very rare timing conditions, an mpiControlReset(...) could lock-up the PCI bus for half a second. This was caused by an internal controller flag that was monitored by the firmware during a reset. This potential problem was corrected in firmware version 347B1.

### ***Modification of Velocity Integrator term in PIV loop*** **MPI 639**

In firmware version 310, Kiv was not multiplied optimally. This resulted in the contribution of the integrator actually exceeding the limit, because the limit was applied before multiplying by Kiv. This caused nonlinear behavior and integrator windup. This problem was corrected in firmware version 310J1. The integration limit is now applied after summation, which limits the output of the integration portion of the velocity loop.

### ***Kfff bug in PIV algorithm*** **MPI 637**

Friction Feed Forward (Kfff) was incorrectly applied to the filter output in firmware versions 295A3 to 310B3, when using the PIV algorithm. Kfff is applied correctly with the PID algorithm, but in the PIV algorithm, Kfff was added in two places: in the velocity loop and after the velocity loop. As a result of Kfff being incorrectly applied with the PIV algorithm, there is potential for an unexpectedly high output in the direction of commanded motion, which could cause instability. This problem only occurs if Kfff is set to a non-zero value. The default value for Kfff is zero. In the fixed version, Kfff is added only after the velocity loop. This was corrected in firmware version 307C4 and 310J1.

### ***MPIMotionTypeSPLINE motion error*** **MPI 633**

Calling mpiMotionStart(...) with motion type MPIMotionTypeSPLINE generated a profile with a large command position jump near the end of the move. This was caused by an error in the algorithm that looked one point beyond the end of the positions list. As this value was uninitialized, the resultant profile included a potentially large command position jump. This was corrected in the 2000091303 release.

### ***No AT\_TARGET with path motion*** **MPI 630**

In the 2000072802 release AT\_TARGET status and event were not issued during path motion when each axis had different target values. This problem was corrected in the 2000072803 release.

### ***PIV parameter structure mismatch*** **MPI 603**

In the 20000913 release, a mismatch between the DSP PIV Algorithm and the MEIFilterGainPIV structure existed. This mismatch caused the last 15 PIV filter coefficients to be incorrectly labeled. This mismatch was fixed in the 20001103 release.

### ***meiFrameBufferLoad(...) empty limit disable bug*** **MPI 584**

In previous versions, a boundary condition existed in the path motion algorithm, which occasionally caused the controller to stop an axis with an unexplained error state. The problem occurred when the last frame buffer load was exactly 64 frames. The load algorithm did not check to see if the 64th frame was the last frame. This caused a buffer low event, stopping the axes, and triggering a false EMPTY\_LIMIT. This was corrected in version 20010131.

### ***Position Error requires two ActionRESETS*** **MPI 574**

In previous versions, when an axis was ABORTed and there is a position error, mpiMotionAction(..., MPI-ActionRESET) did not always clear the position error properly. Sometimes, mpiMotionAction(...) needed to be called twice. This problem was corrected in firmware version 320A1.

### ***User Limit race condition*** **MPI 565**

In previous versions, a possible race condition existed between the MPI and the XMP firmware with user

limits. The problem occurs when the XMP executes a limit condition while the MPI is writing to the limit structure. If the MPI sets the outputPtr to zero while disabling an enabled limit there is the possibility of disabling the execution of the XMP's DSP.

This problem was corrected by adding a handshake state variable between the DSP and the MPI. The possible states are IDLE, MODIFY and DONE. In the MPI, when meiMotorEventLimitSet(...) is called, it waits for the synchronization word (modifyState) to be IDLE. If the state is IDLE, then the MPI sets the state to MODIFY, writes the limit structure to XMP memory, then sets the state to DONE. The firmware will not process the data if the state is not IDLE. This problem was corrected in version 20010105.

### ***DAC limit and OutputOffset Changes***

**MPI 562**

In previous firmware versions, when configured for PID or PIV filter mode, the OutputOffset filter coefficient was added to the output value after the bipolar output limits were checked. For example, if the PID or PIV filter output was 32767 (10 volts) and the OutputOffset is 0, the DAC value is 32767. If OutputOffset was 1, the DAC value is 32768 (-10.0) volts. This problem was corrected by bounding the filter output value to 16 bits, before writing to the DAC. Also, the OutputOffset is now applied before the output limits. This problem was corrected in firmware version 320A1 and 310J1.

### ***Encoder termination always set***

**MPI 551**

In version 200000913, encoder termination was always active and could not be cleared. Encoder termination can now be turned on or off by using the encoder termination field in the MEIMotorConfig{...} data structure when calling the MEIMotorConfigSet(...) method. This bug was fixed in version 2000091302 software.

### ***Multi-axis motion modify during acceleration***

**MPI 525**

In version 310B3 firmware, if two axes were accelerating towards a target position (in the same Motion Supervisor) and the motion was modified to reach a further target position, the acceleration changed to 0.0 and after a while, the acceleration resumed back to its original commanded value. This problem was caused by the point-to-point algorithm for multiple axes. This problem was corrected in the new S-Curve/Trapezoidal algorithm, which was implemented in firmware version 325B1.

### ***mpiMotionAction(RESUME) does not resume motion***

**MPI 524**

In firmware version 310B3, when a STOP occurred, the firmware decelerated the axis by decreasing the feedrate. Once the feedrate became 0, the axis settled. Once settled, the done bit was set and the axis entered the IDLE state. A MPIActionRESUME cleared the STOP bit, but did not change the state of the axis. Since the axis was still in the IDLE state, the MS set the feedrate to 0, so that the axis would not resume motion. This problem was fixed in version 310B5 and 325A1.

### ***Zero time value in S\_CURVE Frame from MotionModify***

**MPI 519**

In previous versions, if mpiMotionModify(...) is called during the first sample of the previous motion profile, the firmware would incorrectly calculate zero for the frame execution time. This causes the motion profile to halt execution. This was corrected in firmware version 311A1.

### ***mpiCaptureConfigGet/Set Bug***

**MPI 482**

In previous MPI versions, mpiCaptureConfigGet(...) did not return proper values for mask and pattern. This was corrected in version 20010119.

# 6 MPI/MEI Libraries: Outstanding Bugs, Limitations

## 6.1 Known Bugs

### **Win2000 Device Driver System Stand by Error**

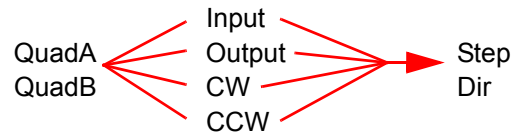
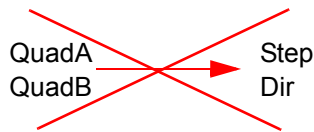
**MPI 741**

The XMP Windows 2000 device driver will not allow a host system go into "Standby" or "Hibernation" mode. This bug will be corrected in a subsequent release.

### **Motor XCVR configuration QUADA dependence**

**MPI 508**

Changing XCVRA or XCVRB from QuadA or QuadB, to Step or Dir will result in XCVRA or XCVRB remaining configured for QuadA or QuadB. In order to change XCVRA or XCVRB from QuadA or QuadB to Step or Dir, first change QuadA or QuadB to any other value except Step and Dir, such as Input, Output, CW, or CCW. Once it has been changed to one of these other values, it is possible to configure the XCVR's for Step and/or Dir. (See 564 in section 4.21 Motion Console: Open Issues)



## 6.2 Known Limitations

### ***Motion Modify Overshoots***

**MPI 836**

An overshoot will occur when mpiMotionModify(...) is called:

- with the same motion parameters that were used with the mpiMotionStart(...) method.
- with a deceleration greater than the acceleration.
- during the deceleration part of the move.

### ***DRate limited in firmware***

**MPI 703**

The Filter object's DRate (derivative sub-sampling rate) is limited to a range from 0 to 7. Values greater than 7 are not valid.

### ***WinNT Driver Invalid Board Number Bug***

**MPI 568**

The MEIXMP device driver can support a maximum of 8 XMP-Series controllers.

### ***Firmware support for jogging***

**MPI 554**

The MPI has a motion type for jogging (MPIMotionTypeJOG), but presently the firmware does not support it.

### ***Brake Enable/Disable Delay***

**MPI 533**

The Brake feature sets the User Output to an Active state when an Abort Event occurs. The "Brake Delay" specifies the amount of time to delay between the Abort Event and setting the User Output bit. Presently, the only way to clear the Brake is with a Controller Reset.

### ***Frame buffer overwritten by Start/Modify append***

**MPI 532**

Each axis has a 128 frame buffer (FIFO). Motion Start and Motion Modify calls will load up to 10 frames. No provision has been made to check if the new frames will overwrite currently executing frames. This could happen after about 12 Start/Modify calls are made with the APPEND attribute.

### ***Gear Ratio with Stepper Axes***

**MPI 522**

The MEIXmpAxisGear firmware feature only supports servo motor types. The axis gear feature does not support step motor types.

### ***MEI Motion Attribute limitations in Sequences***

**MPI 488**

The following MEI motion attributes are supported in motion sequences:

- MEIMotionAttrMaskFINAL\_VEL
- MEIMotionAttrEVENT

Other motion attributes will be available in future releases.

### ***MPI motion attribute limitations in Sequences***

**MPI 487**

The following MPI motion attributes are supported in motion sequences:

- MPIMotionAttrMaskID
- MPIMotionAttrMaskDELAY

Other motion attributes will be available in future releases.

### ***PT/PVT Motion Types currently unsupported in Motion Sequences*** **MPI 486**

These motion types will be available in future releases.



## ***BSpline motion***

**MPI 470**

AUTO\_START is not yet supported for BSpline motion.

## ***mpiCommandPositionSet(...) failure***

**461**

mpiCommandPositionSet(...) does not set the command position

- when the axis is in a MOVING or ERROR state
- after a STOP, E\_STOP, or ABORT event has occurred

The mpiCommandPositionSet(...) does not return an error code when called during these conditions.

**NOTE:** a call to mpiMotionAction(..., RESET) makes it possible to set the command position.

## ***Non-integer relative moves***

**442**

When successive non-integer length relative motions are commanded, the fractional portion is truncated and discarded. This may cause problems if the fractional value needs to be summed over multiple moves.

## ***Axis jumps on frame buffer underflow***

**435**

If E-stop deceleration rates are not set high enough to stop within the number of frames specified by the empty frame limit, the axis jumps on a frame underflow. The axis will E-stop along the path of the last frames in the buffer, then continue onto the next frames (which are the frames from 128 frames ago). This can potentially cause a dangerous condition.

## ***Default Commutation OutputLevel is non-zero***

**433**

The default open-loop commutation output level is set to 8192, representing 2.5 V at the DACs. This level can damage a motor winding and drive. Since a drive gain and motor safe current levels are unknown, the correct value should be 0.0, so that the open-loop current level may be intentionally set by the user.

## ***mpiCommandCreate(...) fails with MotionModify***

**CRN 399**

MPIMotionModify is not supported in sequences.

## ***MS/Axis Mapping Error Code***

**CRN 353**

Misleading time-out errors are returned when trying to manipulate improperly mapped motion supervisors.

## ***Motion Modify with Delay***

**CRN 289**

MPI motion with Modify is not supported with the Delay attribute.

## ***Motion Events with Motion Supervisors sharing axes***

**CRN 243**

When using multiple Motion Supervisors that share axes, Motion events (Done, AtVelocity) are sent to both Motion objects, no matter which Motion Supervisor commanded the motion. This occurs, because the Motion events are derived from the Motion Supervisor status, which is derived from each axis' status.

## ***Software Position Limit can produce both Positive and Negative limit events***

**CRN 13**

When the distance between the positive and negative limit configurations exceed 32 bits (4,294,967,296 counts), both limits are triggered. The distance between the positive and negative software position limits must be less than 32 bits (4,294,967,296 counts).

## ***Long point-to-point moves***

**06**

The XMP firmware velocity frame execution time cannot exceed 16,384,000 samples. With the sample rate configured for 2000 (default), the maximum velocity time is 2.27 hours. If the commanded motion exceeds the maximum frame time, the axes will stop abruptly after 16,384,000 samples. The motors will still maintain servo control and no errors are reported.

## 7 Addendum

This section describes the changes between version 20020117.1.6.1.3 and 20020117.1.6.1.5.

### 7.1 mpiMotionEventNotify Causes Crash with RELEASE library

**MPI2347**

If a motion object is created with no axes and the motion object is passed to mpiMotionEventNotify(...) using the RELEASE library, mpiMotionEventNotify(...) fails with a memory protection fault.

This problem is caused by accessing the axis handles associated with a motion object when no axis handles are available.

The MPI RELEASE library is now compiled with the MEI\_VALIDATE option to verify all object handles before using them.