

Motion Control API Programming interface

<u>System Function</u>	<u>General Function</u>		
MCC_InitSystem()	MCC_EnableBlend()	MCC_SetPGain()	MCC_SetFeedSpeed()
MCC_CloseSystem()	MCC_DisableBlend()	MCC_GetPGain()	MCC_SetPtPSpeed()
MCC_CreateGroup()	MCC_CheckBlend()	MCC_JogPluse()	MCC_SetAccTime()
MCC_CloseAllGroup()	MCC_EnableInPos()	MCC_JogSpace()	MCC_GetAccTime()
MCC_ClearError()	MCC_DisableInPos()	MCC_JogConti()	MCC_SetDecTime()
MCC_GetErrorCode()	MCC_GetInPosStatus()	MCC_HoldMotion()	MCC_GetDecTime()
MCC_UpdateParam()	MCC_OverrideSpeed()	MCC_ContiMotion()	MCC_SetPtPAccTime()
MCC_SetSysMaxSpeed()	MCC_GetOverrideRate()	MCC_AbortMotionEx()	MCC_GetPtPAccTime()
MCC_GetSysMaxSpeed()	MCC_OverridePtPSpeed()	MCC_SetAbsolute()	MCC_SetPtPDecTime()
	MCC_GetPtPOVERRIDERate()	MCC_SetIncrease()	MCC_GetPtPDecTime()
<u>Instruction Function</u>	MCC_SetCompParam()	MCC_SetAccT()	MCC_SetMaxPulseSpeed()
MCC_Line()	MCC_SetOverTravelCheck()	MCC_GetAccType()	MCC_GetMaxPulseSpeed()
MCC_ArcXYZ()	MCC_GetOverTravelCheck()	MCC_SetDecType()	MCC_SetMaxPulseAcc()
MCC_ArcXYZUVW()	MCC_Home()	MCC_GetDecType()	MCC_GetMaxPulseAcc()
MCC_ArcXY()	MCC_GetGoHomeStatus()	MCC_SetPtPAccType()	MCC_GetCurPos()
MCC_ArcXYUVW()	MCC_SetInPosToleranceEx()	MCC_GetPtPAccType()	MCC_GetPulsePos()
MCC_ArcThetaXY()	MCC_GetInPosToleranceEx()	MCC_SetPtPDecType()	MCC_EnableDryRun()
MCC_CircleXY()		MCC_GetPtPDecType()	MCC_DisableDryRun()
MCC_CircleXYUVW()			MCC_CheckDryRun()
MCC_HelicaXY_Z()			
MCC_PtP()			
MCC_DelayMotion()			

Introduction

MCCL is a real-time multiplex Motion Control API (including LIB and DLL) provides users with simple calling Motion Control API. User can call related API under graphic control software or application program when developing man-machine interface, for speed development of integration system. Coupled with EPCIO Series motion control module will provide Windows 98se/NT/2000、Windows XP/XP Embedded versions.

System Environment

- EPCIO-based motion modules
 - Windows 98se
 - Windows NT
 - Windows 2000
 - Windows XP
 - Windows Vista

Development Environment

- Borland C++ Builder (BCB)
- Visual C++ (VC++)
- Visual Basic (VB)
- Visual C# (VC#)

Functions

- Number of axes : 3+3 (auxiliary axis)
- Line、Arc、Circle interpolation
- PtP interpolation
- Motion delay
- Hold / Continue / Abort control
- Continue / Space / Pulse mode jogging
- Accel/Deceleration curve : Trapezoid / S_curve
- In-position check
- Position error tolerance setting
- Gain setting
- Pitch BackLatch Positioning Compensation
- Speed override
- Home
- OverTravel Checking
- Quit moving

Procedure

```
# include "MCCL.h"
MCC_InitSystem()
    ↓
MCC_Line()
    ↓
MCC_PtP()
    ↓
.....
MCC_CloseSystem()
```

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