

# libmip Sample Application Reference Manual

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# Chapter 1

## libmip Sample Application Class Index

### 1.1 libmip Sample Application Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

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## Chapter 2

# libmip Sample Application Class Documentation

### 2.1 MyMip Class Reference

```
#include <MyMip.h>
```

#### Public Member Functions

- **MyMip** (MipManager \*mm, const std::string &device, int baudrate, int deviceid)  
*Constructor.*
- void **Initialize** ()  
*Initialize.*
- void **Terminate** ()  
*Terminate.*
- virtual void **OnReceivedReadAxisStatus** (int cmdid, eAxisStatusFlags status)
- virtual void **OnReceivedReadError** (int cmdid, eError error)
- virtual void **OnReceivedClearError** (int cmdid)
- virtual void **OnReceivedReadWarning** (int cmdid, eWarning warning)
- virtual void **OnReceivedClearWarning** (int cmdid)
- virtual void **OnReceivedReadVersion** (int cmdid, int command\_interpreter\_version, int runtime\_library\_version, int hardware\_revision, int bootrom\_version, int application\_number, int application\_version)
- virtual void **OnReceivedSetPosVelocity** (int cmdid)
- virtual void **OnReceivedSetWaitMode** (int cmdid)
- virtual void **OnReceivedMoveAbsolute** (int cmdid)
- virtual void **OnReceivedMoveRelative** (int cmdid)
- virtual void **OnReceivedStopMotion** (int cmdid)
- virtual void **OnReceivedFindHomeSys** (int cmdid)
- virtual void **OnReceivedReadPosition** (int cmdid, int position)
- virtual void **OnReceivedReadVelocity** (int cmdid, int position)
- virtual void **OnReceivedReadVelocityMean** (int cmdid, int position)

- virtual void **OnReceivedReadCurrent** (int cmdid, int position)
- virtual void **OnReceivedCheckCRC** (int cmdid, bool ok, int crc)
- void **OnEvent** ()
- int **AngleToPosition** (double angle)

*Converts positions to angles.*

- double **PositionToAngle** (int position)

*Converts angles to positions.*

- double **ShortestAngle** (double anglemust, double anglenow)

*Returns the angle associated with the shortest motor movement.*

- double **DegToRad** (double angle)

*Converts degrees to radians.*

- double **RadToDeg** (double angle)

*Converts radians to degrees.*

### 2.1.1 Detailed Description

Sample Mip class.

This class implements the desired functionality. It sends commands to the MIP device and processes the received replies. Furthermore, it periodically checks the motor control status.

The documentation for this class was generated from the following file:

- MyMip.h



## 2.2 SampleApplication Class Reference

```
#include <SampleApplication.h>
```

### Public Member Functions

- **SampleApplication** (int argc, char \*\*argv)  
*Constructor.*
- **~SampleApplication** ()  
*Destructor.*
- virtual void **OnInitialize** ()
- virtual void **OnTerminate** ()

#### 2.2.1 Detailed Description

Sample application to demonstrate how to use the libmip.

The documentation for this class was generated from the following file:

- SampleApplication.h

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