

## PiezoPiCtrl Tango Cpp Class

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### PiezoPiCtrl Class Identification :

Contact : at mail.desy.de - tnunez  
Class Family : Motion  
Platform : Unix Like  
Bus : Socket  
Manufacturer : PI  
Manufacturer ref. :

### PiezoPiCtrl Class Inheritance :

- [Tango::DeviceImpl](#)
  - PiezoPiCtrl

### PiezoPiCtrl Class Description :

Class connecting to the Pi Piezos

## PiezoPiCtrl Properties :

There is no class properties

Device Properties			
Name	Description	Type	Default Value
PortNb	RS232 Port Number	int	0
IpAddr	Ip address of the terminal server	String	none
SimulationMode	0 -> real mode, 1 -> simulation mode	int	0
USBPort	This property can be set to e.g. /dev/ttyUSB0 to specify how the PiezoPiCtrl is connected. The default is None.	String	None
Speed	57600 (default), 115200 or 19200	int	57600
SerialNumber	Serial number for distinguish between Piezos connected via USB.	String	0
SocketTimeoutus	Socket timeout in us.	int	100000

PiezoPiCtrl Class Commands				
Name	Input type	Output type	Level	Description
<a href="#">State</a>	DEV_VOID	DEV_STATE	OPERATOR	This command gets the device state (stored in its <i>device_state</i> data member) and returns it to the caller.
<a href="#">Status</a>	DEV_VOID	CONST_DEV_STRING	OPERATOR	This command gets the device status (stored in its <i>device_status</i> data member) and returns it to the

				caller.
<a href="#">WriteSocket</a>	DEV_STRING	DEV_VOID	OPERATOR	Send a command to the Socket
<a href="#">WriteReadSocket</a>	DEV_STRING	DEV_STRING	OPERATOR	Write a command to the socket and get the answer.
<a href="#">CloseSocket</a>	DEV_VOID	DEV_VOID	OPERATOR	Close socket connection.
<a href="#">ReadMotionStatus</a>	DEV_VOID	DEV_LONG	OPERATOR	Read motion status, als bit mapped. 0 no axis moving. Only effective in close loop operation (servo on).

### **Command State :**

This command gets the device state (stored in its *device\_state* data member) and returns it to the caller.

<b>State Definition</b>		
Input Argument	Tango::DEV_VOID	none.
Output Argument	Tango::DEV_STATE	State Code
DisplayLevel	OPERATOR	..
Inherited	true	..
Abstract	true	..
Polling Period	Not polled	..
Command allowed for	All states	..

## Command Status :

This command gets the device status (stored in its *device\_status* data member) and returns it to the caller.

Status Definition		
Input Argument	Tango::DEV_VOID	none.
Output Argument	Tango::CONST_DEV_STRING	Status description
DisplayLevel	OPERATOR	..
Inherited	true	..
Abstract	true	..
Polling Period	Not polled	..
Command allowed for	All states	..

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## Command WriteSocket :

Send a command to the Socket

WriteSocket Definition		
Input Argument	Tango::DEV_STRING	Command
Output Argument	Tango::DEV_VOID	
DisplayLevel	OPERATOR	..
Inherited	false	..
Abstract	false	..
Polling Period	Not polled	..
Command allowed for	All states	..

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## **Command WriteReadSocket :**

Write a command to the socket and get the answer.

<b>WriteReadSocket Definition</b>		
Input Argument	Tango::DEV_STRING	Command
Output Argument	Tango::DEV_STRING	Answer
DisplayLevel	OPERATOR	..
Inherited	false	..
Abstract	false	..
Polling Period	Not polled	..
Command allowed for	All states	..

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## **Command CloseSocket :**

Close socket connection.

<b>CloseSocket Definition</b>		
Input Argument	Tango::DEV_VOID	
Output Argument	Tango::DEV_VOID	
DisplayLevel	OPERATOR	..
Inherited	false	..
Abstract	false	..
Polling Period	Not polled	..
Command allowed for	All states	..

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### **Command ReadMotionStatus :**

Read motion status, als bit mapped. 0 no axis moving.  
Only effective in close loop operation (servo on).

<b>ReadMotionStatus Definition</b>		
Input Argument	Tango::DEV_VOID	
Output Argument	Tango::DEV_LONG	Motion status
DisplayLevel	OPERATOR	..
Inherited	false	..
Abstract	false	..
Polling Period	Not polled	..
Command allowed for	All states	..

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**There is no attribute defined.**

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**There is no dynamic attribute defined.**

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## PiezoPiCtrl Class States

Name	Description
ON	Connection open.
FAULT	Problems in connection.