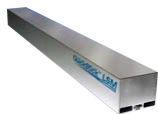


MagneMotion QuickStick



Manufacturer: MagneMotion
 Model Number: MagneMotion-QuickStick
 Web Address: www.magnemotion.com

MagneMotion's QuickStick Linear Synchronous Motor (LSM) transport and positioning systems for large loads provides the assembly automation market a faster, cleaner, and more efficient alternative to conventional linear motion methods or conveyor systems.

Dispenser: Commands

◆ **Startup(pathID)** - Initiate the startup sequence for locating all vehicles on the specified path.

pathID	Integer	Specifies the identifier of the path. 0 - startup all paths. Range of values: 0 to 65536.
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◆ **Reset(pathID)** - Reset all QuickSticks on the specified path. All vehicle records on the path will be deleted. Startup should be executed on the path to bring them to the operational state.

pathID	Integer	Specifies the identifier of the path. 0 - reset all paths. Range of values: 0 to 65536.
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◆ **MoveVehicleToStation(vehicleID, direction, stationID, accelLimit, velocityLimit)** - Move the vehicle to the specified station.

vehicleID	Integer	Specifies the vehicle identifier. Range of values: 1 to 65536.
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direction	Integer	Specifies the direction. 0 - bi-directional; 1 - forward (downstream); 2 - backward (upstream) Range of values: 1 to 65536.
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stationID	Integer	Specifies the station to send the vehicle. Range of values: 1 to 65536.
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accelLimit	Float	Specifies the acceleration and deceleration limit in m/s*s.
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velocityLimit	Float	Specifies the velocity limit in m/s.
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◆ **MoveVehicleToPosition(vehicleID, direction, position, pathID, accelLimit, velocityLimit)** - Move the vehicle to the specified position relative to the start of a string of QuickStick motors.

vehicleID	Integer	Specifies the vehicle identifier. Range of values: 1 to 65536.
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direction	Integer	Specifies the direction. 0 - bi-directional; 1 - forward (downstream); 2 - backward (upstream) Range of values: 1 to 65536.
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position	Float	Specifies the position to move to in meters.
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pathID	Integer	Specifies the identifier of the path. The path must be a non-zero integer which exists in the configuration. Range of values: 1 to 65536.
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accelLimit	Float	Specifies the acceleration and deceleration limit in m/s*s.
velocityLimit	Float	Specifies the velocity limit in m/s.

• **SuspendMovement(pathID)** - Suspend movement on the specified path.

pathID	Integer	Specifies the identifier of the path. 0 - suspend all paths. Range of values: 0 to 65536.
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• **ResumeMovement(pathID)** - Enable movement after the path has been suspended movement.

pathID	Integer	Specifies the identifier of the path. 0 - resume all paths. Range of values: 0 to 65536.
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• **StatusRequest(requestType, id, motorIndex)** - Request status for the specified type.

requestType	Integer	Specifies the request type. 0 - high level controller status; 1 - node controller status; 2 - node status; 3 - path status; 4 - vehicle status; 5 - motor status Range of values: 0 to 5.
id	Integer	Identifier for the request type. 0 - all elements. When request type is 5 (motor status), this field selects the path by ID that the motor reside on and the next byte MotorIndex selects which motor on the selected path ID. Range of values: 0 to 65536.
motorIndex	Integer	This is ignored for request types 0, 1, 2, 3, and 4. 1 - 40 individual motor index on path ID; 0 - all motors on path ID; 255 - all motors with active faults on path ID

• **RequestComponentInfo(componentType, infoType, primaryID, secondaryID)** - Request information on a specific component.

componentType	Integer	Specifies the component type. 0 - high level controller; 1 - node controller Range of values: 0 to 1.
infoType	Integer	Specifies the information type. 0 - version number Range of values: 0 to 0.
primaryID	Integer	Specifies the primary identifier (if applicable)
secondaryID	Integer	Specifies the secondary identifier (if applicable)

Instrument Error

• **InstrumentError(errorCode)** - An error occurred during command execution.

errorCode	Integer	Determines what kind of error occurred.
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