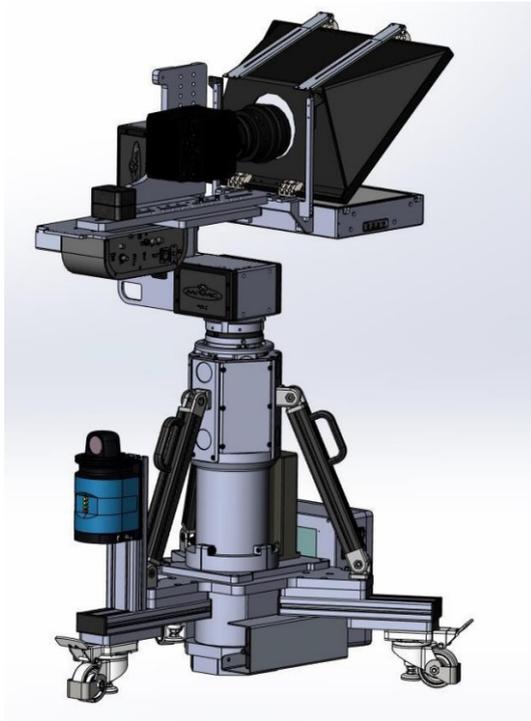




MARK ROBERTS MOTION CONTROL

XY LOCATION SYSTEM



QUICK START GUIDE

QSG Product code: MRMC-2221-00

Product Covered: MRMC-2211-00

XY Location System Quick Start Guide

Product code: MRMC-2221-00

Product Covered: MRMC-2211-00

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Chapter 1 Quick Start



Important safety instructions

To ensure the best from the product, please read this manual carefully. Keep it in a safe place for future reference.

To reduce the risk of electric shock, do not remove the cover from the unit. No user serviceable parts inside. Refer servicing to qualified personnel.

Power and connections

- This unit must be connected to a mains socket outlet with a protective earth connection.
- This unit is not disconnected from the AC power source as long as it is connected to the wall outlet.
- When not using the unit for a long period of time, ensure that the AC power cord is disconnected from the wall outlet.
- The AC wall outlet should be installed near to the unit and be easily accessible.
- Do not plug in or attempt to operate an obviously damaged unit.

General care

- Do not force switches or external connections.
- When moving the unit, disconnect the mains cable and then disconnect the long umbilical cable.
- Do not attempt to clean the unit with chemical solvents or aerosol cleaners, as this may damage the unit. Use a clean dry cloth.
- Do not use around flammable gas. All electrical equipment can generate sparks that can ignite flammable gas.
- Keep away from pets and children. The head has powerful motors that can pinch, so take care not to get your hands trapped in the head or cabling.

- Keep cables tidy. Use cable ties to keep them out of harm's way. If you have a head with slip rings then make use of them; avoid running any cables between the base and the rotating head or camera.

Location

Installation of this unit should be away from sources of excessive heat, vibration, and dust.

Keep the brakes on caster wheels on when using the SLH lift column.

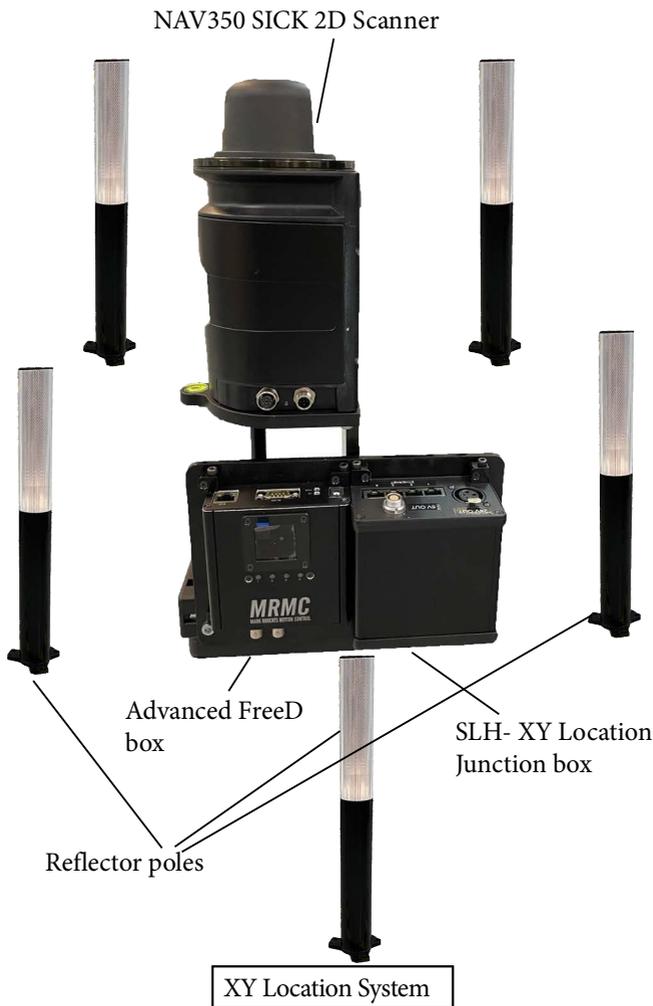
Intellectual property

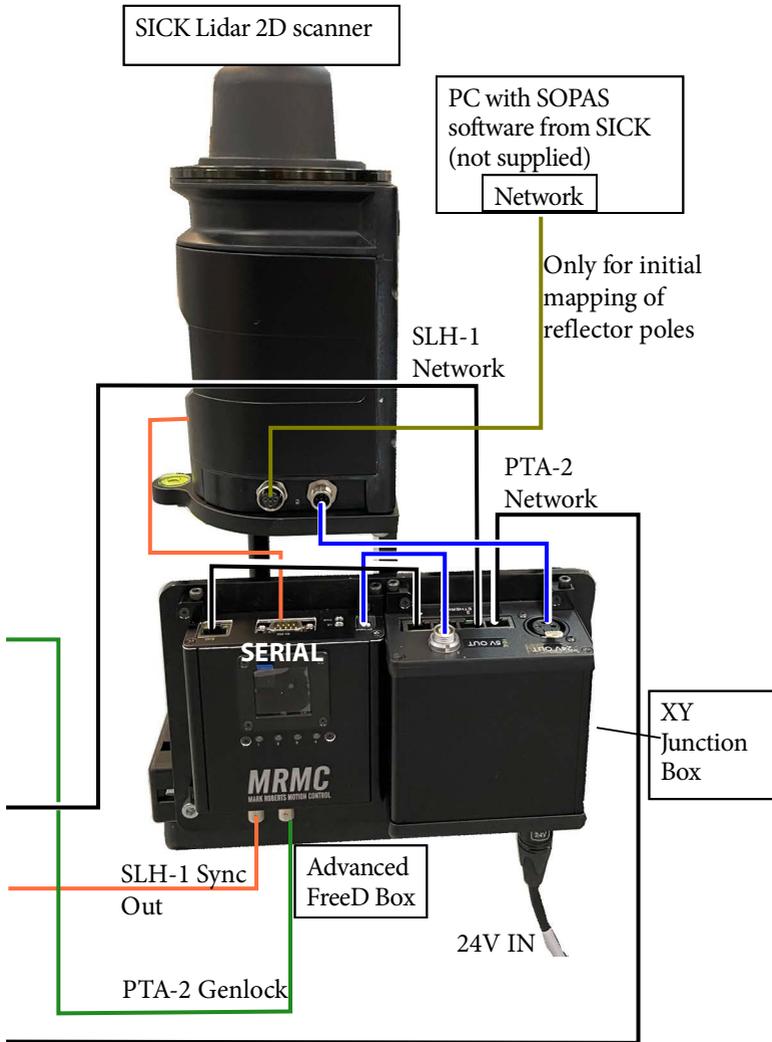
This product includes confidential and/or trade secret property.

Therefore, you may not copy, modify, adapt, translate, distribute, reverse engineer, or decompile contents thereof.

Overview

Thank you for using the XY Location System column from Mark Roberts Motion Control (MRMC). This is an optical locating device which can be used to determine X and Y coordinate locations of items such as Lift Columns, robots and potentially other equipment making it invaluable in indoor studios using Virtual Reality environments. You can use the Ethernet connection on the SLH to connect directly to a PC running the Multi-Head Controller (MHC) or RTL software.





Setting up the Reflector Poles

- The reflector poles should be placed so they are always clearly visible to the laser.
- Every reflector pole visible to the laser must be mapped by the scanner
- To set up the reflector poles around the scanner, spread them but do not arrange them symmetrically.
- Drill holes to secure the reflector poles to the ground only after you are satisfied with the positions.
- Minimise the chance of occlusion to favour accuracy.

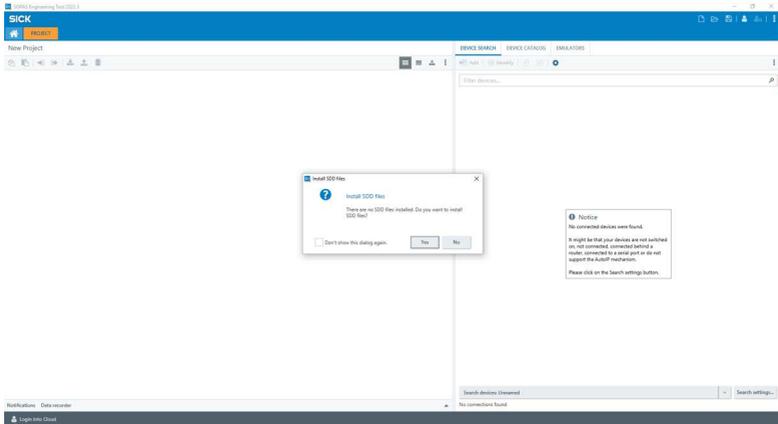
Note

- Reflector poles, or targets, to be well secured before mapping.
- 3 or more must be in the field of view when Scanner is operating
- If a target is moved or damaged, remove or cover completely until it can be re-mapped.

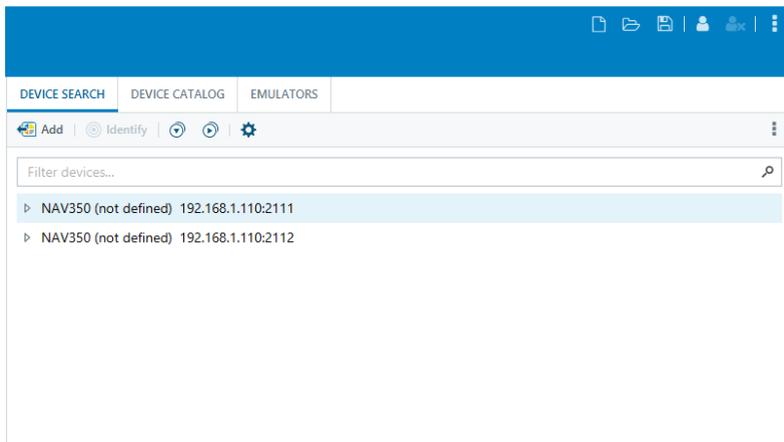
Setting up the 2D scanner

1. Download and install the scanner configuration app. At the moment of that manual writing SOPAS Engineering Tool resides here: <https://www.sick.com/be/en/sopas-engineering-tool/p/p367244>
2. Before running the installed app make sure you plugged the green 4W M12 SICK network cable between 2D scanner and PC or laptop. Ensure that the Advanced FreeD box power supply jack is unplugged. 2D Scanner should be powered on and reflectors poles should be placed in position.
3. Setting up the 2D scanner in the app:

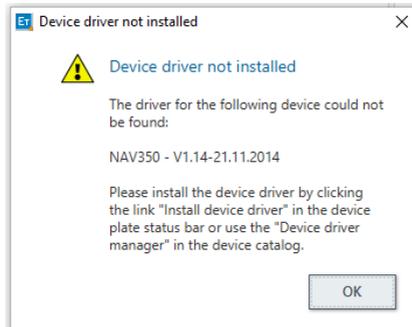
3.1 After application launch the following window appears. Here, click No.



3.2 In the following window, double-click on the top position in the list of available scanners on the right hand side of the screen.



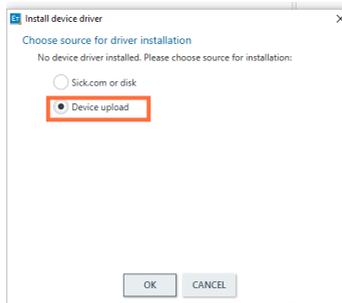
3.3 In the following window, click OK.



3.4 Select **Install Device Driver**.



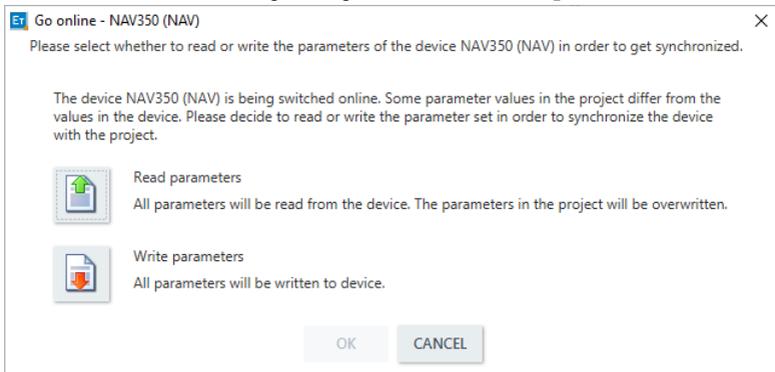
3.5 In the following window, select Device upload and click OK to upload device driver from the device itself.



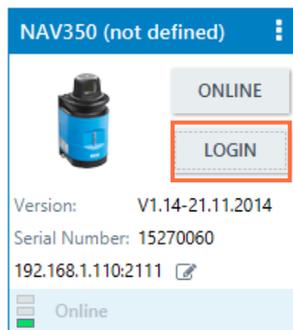
- 3.6 In the following screen, click on OFFLINE button (which makes the scanner to go online).



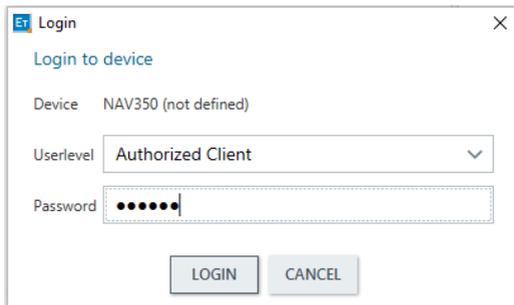
- 3.7 In the following dialog box, click on read parameters.



- 3.8 In the following screen, click on the LOGIN button (on the left hand side of the screen).

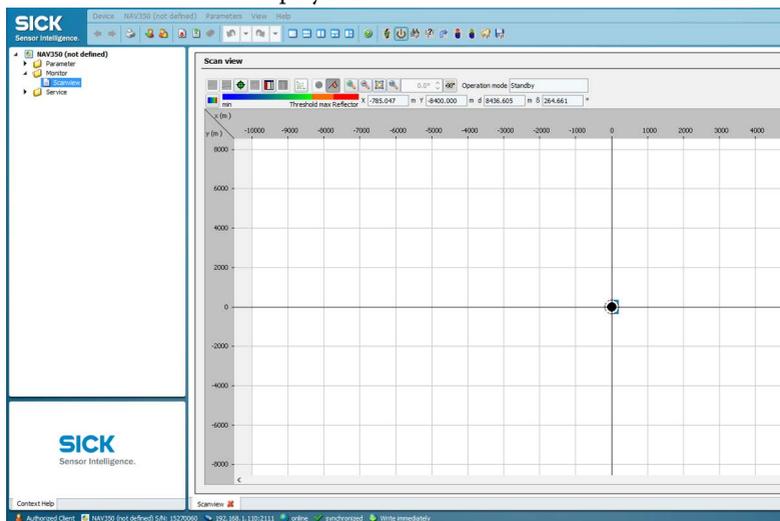


- 3.9 Select Userlevel which should be Authorized Client. Enter password **client** and click the LOGIN button.



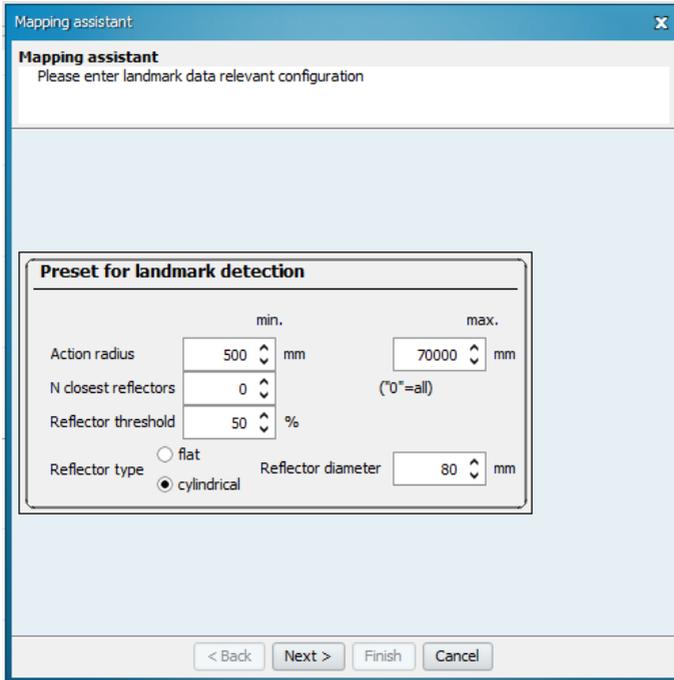
- 3.10 Double-click on scanner image on the left hand side of the screen.

- 3.11 Here we double-click on Monitor and then double-click on Scanview to display the view of the scan from the scanner.



- 3.12 Click Switch to mapping mode  button on the toolbar on top of the screen. During mapping mode make sure that SLH column is located in its zero X,Y, Angle position.

3.13 Check the following settings make sure they are the same and click on Next button.



3.14 In that window we check the following settings make sure they are the same. DOUBLE-CHECK those numbers and check boxes to ensure accurate functioning of the system. Click the

Next button. The distance between the scanner and SLH column is 350mm.

The screenshot shows a software window titled "Mapping assistant" with a close button (X) in the top right corner. Below the title bar, the text "Mapping assistant" and "Please enter mapping relevant configuration" is displayed. The main area is titled "Preset for mapping" and contains several configuration fields:

- Current layer:** A dropdown menu set to "0".
- X-Position:** A text input field containing "0" followed by a unit dropdown set to "mm".
- Y-Position:** A text input field containing "350" followed by a unit dropdown set to "mm".
- Orientation:** A text input field containing "270000" followed by a unit dropdown set to "1/1000 Grad".
- Number of scans for mean value calculation:** A text input field containing "50".
- negative mapping (commit only new reflectors to layout):** An unchecked checkbox.
- Usage of the result:** Two radio buttons: "Replace in current layer" (selected) and "Append to current layer".
- Download data after mapping to device immediately:** A checked checkbox.

At the bottom of the dialog, there are four buttons: "< Back", "Next >", "Finish", and "Cancel".

If scanner is installed on the front leg then do the settings as per above graphic.

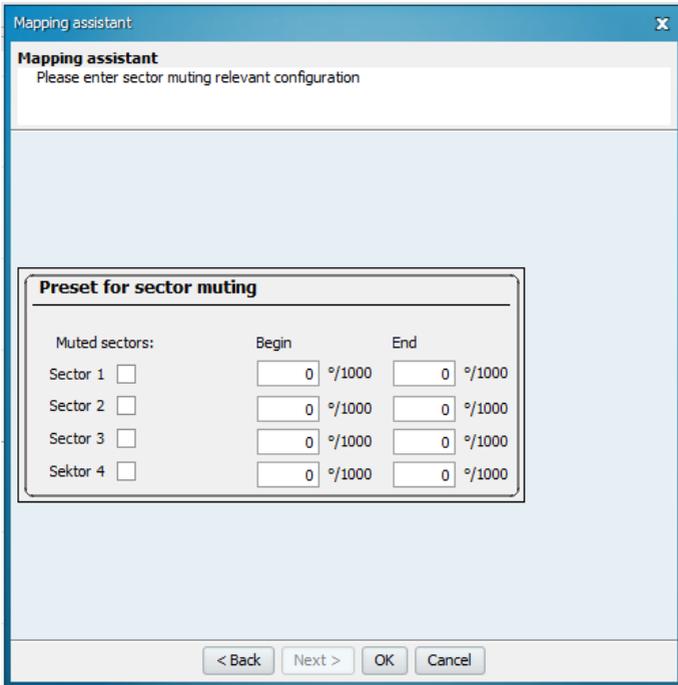
If scanner is installed on the rear right leg, then use the following settings:

- X = 303mm
- Y = -174mm
- Angle = 150000

If scanner is installed on the rear left leg, then use the following settings:

- X = -303mm
- Y = -174mm
- Angle = 30000

3.15 Click OK in the following window.



3.16 After waiting a bit until mapping is completed click on Switch to Navigation Mode () button

3.17 Click Next in the following window.

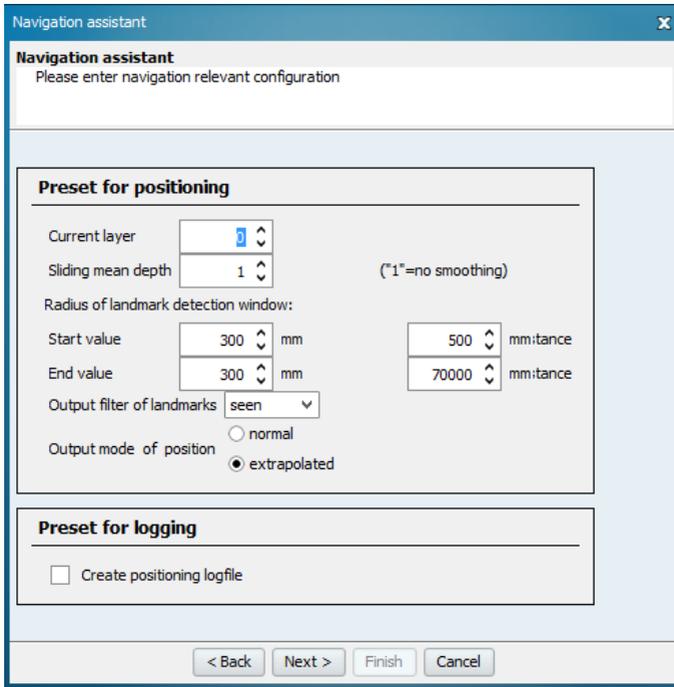
The screenshot shows a software window titled "Navigation assistant" with a close button (X) in the top right corner. Below the title bar, the text "Navigation assistant" is followed by the instruction "Please enter landmark data relevant configuration".

The main content area features a box titled "Preset for landmark detection" with a horizontal line underneath. Inside this box, the following settings are displayed:

- Action radius:** A spinner box set to "500" mm, with "min." above it and "mm" to its right.
- N closest reflectors:** A spinner box set to "0", with "max." above it and "mm" to its right. A note below it says "(*'0'=all)".
- Reflector threshold:** A spinner box set to "50" %.
- Reflector type:** Two radio buttons: "flat" (unselected) and "cylindrical" (selected).
- Reflector diameter:** A spinner box set to "80" mm.

At the bottom of the window, there are four buttons: "< Back", "Next >", "Finish", and "Cancel".

3.18 Click Next in the following window.



Navigation assistant

Navigation assistant
Please enter navigation relevant configuration

Preset for positioning

Current layer: 0

Sliding mean depth: 1 (*1"=no smoothing)

Radius of landmark detection window:

Start value: 300 mm 500 mm;tance

End value: 300 mm 70000 mm;tance

Output filter of landmarks: seen

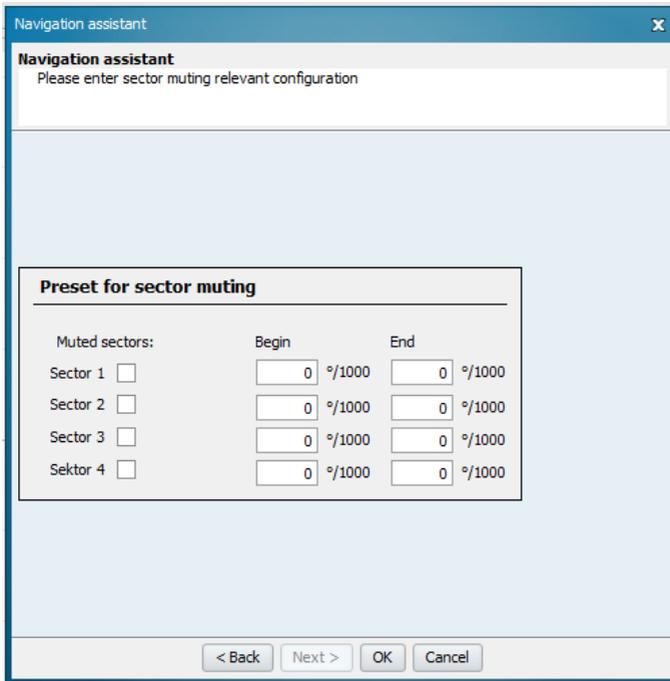
Output mode of position:
 normal
 extrapolated

Preset for logging

Create positioning logfile

< Back Next > Finish Cancel

3.19 Click OK in the following window.

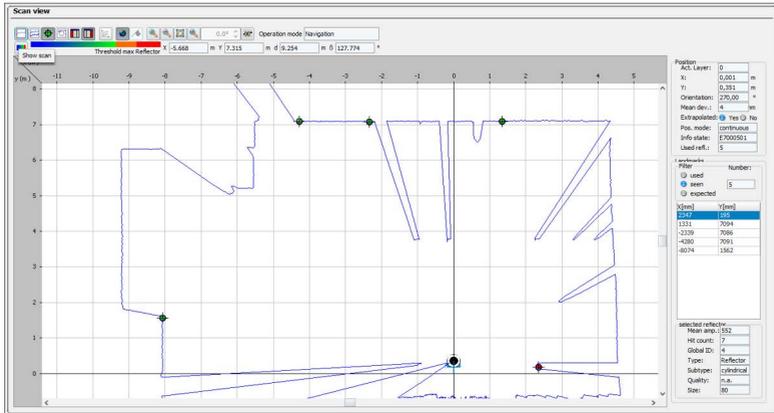


3.20 Click on Show Right Panel button ().

3.21 Click on Show Landmarks button ().

3.22 On the right to panel we can see if mapping has been done correctly. We can see current 2D scanner position which is X=0m, Y=0.35m, Orientation 270.00 deg. If numbers differ significantly mapping can be done again from step 3.13 making sure that device is in standby mode (switch by button

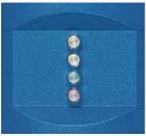
in toolbar). It also shows the landmarks (reflector poles) that can be seen at the moment by the scanner.



There are two useful buttons: Show Scan () and Zoom auto (). Those allow to see what 2D scanner is “seeing” at the moment.

- 3.23 To complete mapping procedure click on Switch to Standby Mode button (). After this network cable can be unplugged from 2D scanner and merge box (advanced sync box) power jack can be plugged back.

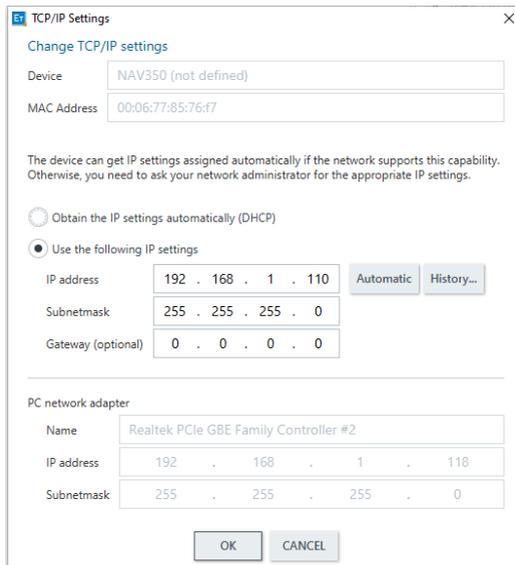
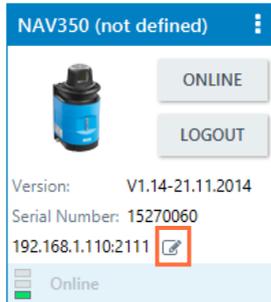
LEDs indications

	Yellow LED (1)	Yellow LED (2)	Green LED	Red LED	Meaning
 <p>Yellow (1) Yellow (2) Green Red</p>	Off	Off	Off	Off	Device switched off. No supply voltage.
	On	On	On	On	LED test for 5 s after switching on. The output signal switching device is active.
	Off	On	Any	Any	A command is being processed
	Off	Any	Flashing 1 Hz	Any	Stand by
	Off	Any	Flashing 4 Hz	Any	Measurement mode
	Flashing 4 Hz	Off	Flashing 1 Hz	Off	Firmware Update
	Any	Any	Any	On	System error in the device For information on troubleshooting see section 8.3 "Troubleshooting and rectification" on page 61

Setting up 2D Scanner's IP address

In order to connect properly, the host PC and the Device must be in the same IP range.

IP address of the scanner can be adjusted at any point by clicking on pen sign on the right from current scanner's IP address.



SLH and PTA2 FreeD setup

Ensure that your system consisting of SICK 2D scanner, advanced FreeD box, SLH and PTA-2 is connected. Make sure that SLH and PTA-2 is supplied with a sync signal source. Make sure the system is powered on before FreeD configuration process. Use the USB cable to connect PC or laptop to the FreeD Box. To simplify the FreeD box configuration, a configuration app can be used with it.

1. Run FreeD_Merge_Box.exe file and the following window should appear.

The screenshot shows a software window titled "FREED MERGE BOX : VERSION 1.2". The window contains the following elements:

- A header bar with a logo, the title, and window control buttons (minimize, maximize, close).
- A text label: "Always select port to Open the serial Port".
- A "Serial_Port" dropdown menu showing "COM24" and a "Click To Refresh Ports" button.
- A "Set Board ip:" text box.
- A "Version" dropdown menu.
- Two text boxes: "Set Board's Subnet:" and "Set Board's Gateway:".
- Two text boxes: "Source 1 Ip Address:" and "Source 2 Ip Address:".
- Four checkboxes: "Merge x", "Merge y", "Merge Z", and "Not Implemented".
- A "Board's Port:" text box.
- A "No_Of_Destinations" dropdown menu showing "5".
- Seven pairs of text boxes for destinations: "Destination-1 IP:" and "Destination-1 Port:" through "Destination-7 IP:" and "Destination-7 Port:".
- Four buttons: "Debug Status" (showing "0"), "Read Settings", "Save Settings", and "Rail Rotate Setp/2D Scanner Support".
- A note at the bottom: "(Only debug status 3 is implemented and always set debug back to 0 after receiving the information)".

2. Click on Serial Port button to select serial port of the FreeD box. After that you should see current settings of the FreeD box.

FREED MERGE BOX: VERSION 1.2

Always select port to Open the serial Port Version 9.03

Serial_Port: COM24 Click To Refresh Ports Set Board ip: 192.168.1.221

Set Board's Subnet: 0.0.0.0 Set Board's Gateway: 0.0.0.0

Source 1 Ip Address: 0.0.0.0 Source 2 Ip Address: 0.0.0.0

Merge x Merge y Merge Z Not Implemented Board's Port: 55534

No_Of_Destinations: 5

Destination-1 IP: 192.168.1.152 Destination-1 Port: 65535

Destination-2 IP: 0.0.0.0 Destination-2 Port: 31267

Destination-3 IP: 0.0.0.0 Destination-3 Port: 666

Destination-4 IP: 0.0.0.0 Destination-4 Port: 77

Destination-5 IP: 0.0.0.0 Destination-5 Port: 8888

Destination-6 IP: Destination-6 Port:

Destination-7 IP: Destination-7 Port:

Debug Status: 0 Read Settings Save Settings Rail Rotate Setp/2D Scanner Support

(Only debug status 3 is implemented and always set debug back to 0 after receiving the information)

3. Check current settings and make required changes. For example if FreeD box should have IP address 192.168.1.221 and listening port 55535 then type in 192.168.1.221 to the Set Board IP field and 55535 to the Board's Port field

For example if PTA-2 head's IP address is 192.168.1.238, so this IP should be input to the **Source 1 Ip Address** field. If SLH's IP address is 192.168.1.236. Then this IP should be input to the **Source 2 Ip Address** field.

- In PTA-2 + SLH system we merge Z position then Merge Z checkbox should be checked.

For example PC's (for FreeD packets reception) IP Address is 192.168.1.87 and Port is 55535. In that case we populate **Destination-1 IP:** field and **Destination-1 Port:** field accordingly.

The screenshot shows the 'FREED MERGE BOX' application window. At the top, it says 'Always select port to Open the serial Port'. Below this are several input fields and buttons:

- Serial_Port:** A dropdown menu showing 'COM4' and a 'Click To Refresh Ports' button.
- Set Board ip:** An input field containing '192.168.1.221'.
- Set Board's Subnet:** An input field containing '255.255.255.0'.
- Set Board's Gateway:** An input field containing '192.168.1.1'.
- Source 1 Ip Address:** An input field containing '192.168.1.238'.
- Source 2 Ip Address:** An input field containing '192.168.1.236'.
- Board's Port:** An input field containing '55535'.
- Merge options:** Three checkboxes: 'Merge x' (unchecked), 'Merge y' (unchecked), and 'Merge Z' (checked). There is also a 'Not Implemented' checkbox (unchecked).
- No_Of_Destinations:** A dropdown menu showing '1'.
- Destination-1 IP:** An input field containing '192.168.1.87'.
- Destination-1 Port:** An input field containing '55535'.
- Destination-2 IP:** An empty input field.
- Destination-2 Port:** An empty input field.
- Destination-3 IP:** An empty input field.
- Destination-3 Port:** An empty input field.
- Destination-4 IP:** An empty input field.
- Destination-4 Port:** An empty input field.
- Destination-5 IP:** An empty input field.
- Destination-5 Port:** An empty input field.
- Destination-6 IP:** An empty input field.
- Destination-6 Port:** An empty input field.
- Destination-7 IP:** An empty input field.
- Destination-7 Port:** An empty input field.
- Debug Status:** A dropdown menu showing '0'.
- Buttons:** 'Read Settings' and 'Save Settings' buttons.
- Footer note:** '(Only debug status 3 is implemented and always set debug back to 0 after receiving the information)'

- After checking of the current settings click **Save Settings** button to complete FreeD box IP setup.
- After that close (exit) the app.

Setting up FreeD box offsets and enabling the 2D scanner support

1. Click the **Rail Rotate Setup/2D Scanner Support** button. The following screen should appear.

Rail rotate setup & 2D Scanner Support

Scanner On/Off Scanner PAN angle compensation sign: 1

Scanner X offset from the head (mm):

Scanner Y offset from the head (mm):

Scanner angular position compensation(0-360 deg):

Rail X center point of rotation (mm):

Rail Y center point of rotation (mm):

Rail X point of rotation angle measurement(mm):

Rail Y point of rotation angle measurement(mm):

Rail angle of rotation relatively X axis(deg):

Head PAN angle compensation(deg):

Calculated rail rotation angle relatively X axis(deg):

2. Press the **Read Settings** button and the following screen appears.

Rail rotate setup & 2D Scanner Support

Scanner On/Off Scanner PAN angle compensation sign: 1

Scanner X offset from the head (mm):	13.0000
Scanner Y offset from the head (mm):	22.0000
Scanner angular position compensation(0-360 deg):	33.0000
Rail X center point of rotation (mm):	744.0000
Rail Y center point of rotation (mm):	555.0000
Rail X point of rotation angle measurement(mm):	75.0000
Rail Y point of rotation angle measurement(mm):	4.0000
Rail angle of rotation relatively X axis(deg):	555.0000
Head PAN angle compensation(deg):	1.0000
Calculated rail rotation angle relatively X axis(deg):	39.4755°

Read Settings Save Settings

3. Check the Scanner On/Off option.
4. Set **Scanner PAN angle compensation sign** to 1.

At the factory, the scanner is installed on the Front Leg of the SLH. So, the scanner installation configuration is:

- Front Leg
In this case, assign these values to the following parameters:
Scanner X offset from the head (mm) to 0.0
Scanner Y offset from the head (mm) to -350.0
Scanner angular position compensation (0-360 deg) to 90.0
- If scanner is installed on the rear right leg then use the following settings:
Scanner X offset from the head (mm) to -302.0

Scanner Y offset from the head (mm) to 174.0

Scanner angular position compensation (0-360 deg) to 210.0

- If scanner is installed on the rear left leg then use the following settings:

Scanner X offset from the head (mm) to 302.0

Scanner Y offset from the head (mm) to 174.0

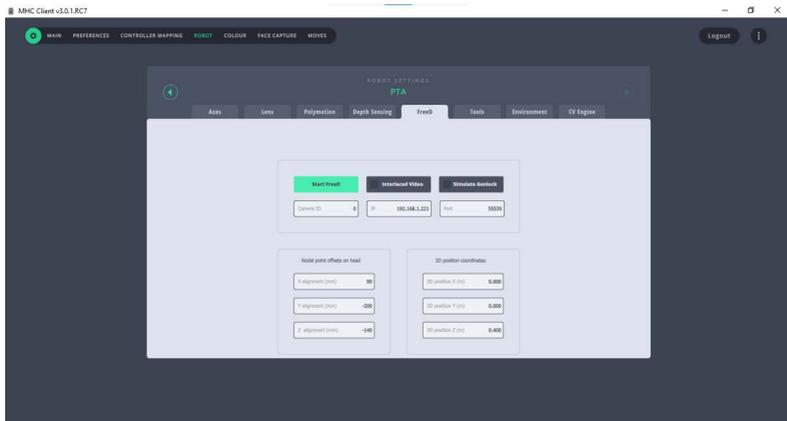
Scanner angular position compensation (0-360 deg) to 330.0

All the remaining fields except the last one (which is read only) should be set to 0.0

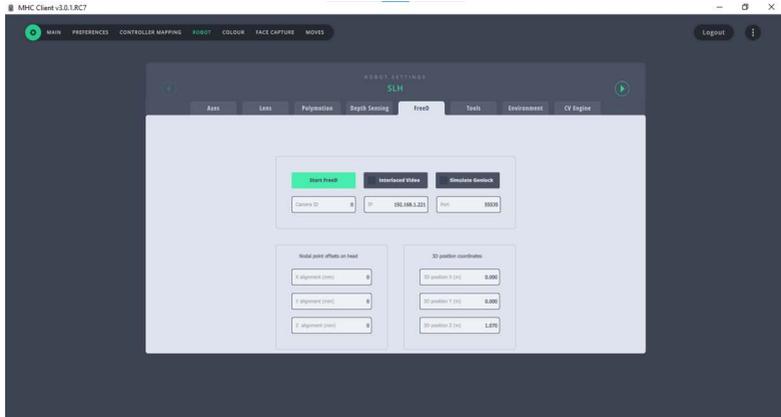
Note that positive PAN angles direction should be CLOCKWISE.

Configuring FreeD Box's IP in MHC for PTA-2 and SLH-1

1. Launch MHC. Log in as Admin. In Network Setup, add the PTA-2 head and add SLH-1 as the 'child' of PTA-2.
2. Log in as 'Engineer' and navigate to **Settings** → **Robot** → **FreeD** for PTA-2 head. Enter FreeD Box IP and its Port to the corresponding fields in MHC for the PTA-2 head. For example,



3. Enter FreeD Box IP and its Port to the corresponding fields in MHC for SLH. For example,



Setting up FreeD offsets in MHC

Setting up Z room offset on SLH.

1. Ensure you got correct scaling factor on the lift column. It might be found in **MHC Server** → **Axis Settings**.

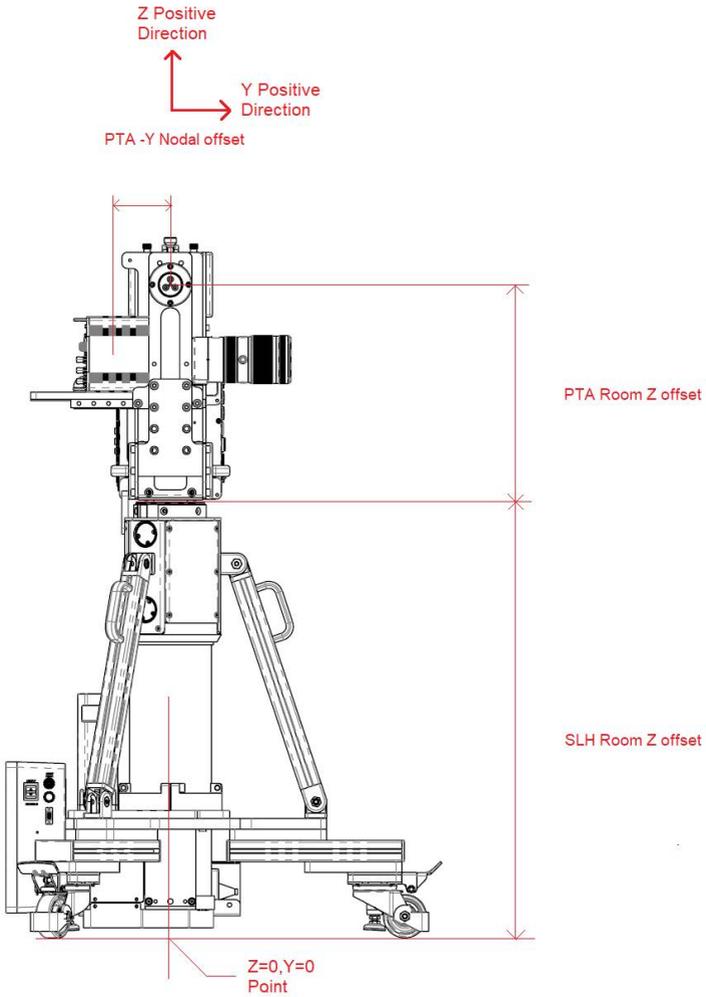
Axis Settings
✕

Motor type:	<input type="text" value="CAN"/>	<input type="text" value="Head 1"/>	<input type="button" value="Connected"/>
Scaling:	<input type="text" value="1.59781e-05"/>	<input type="text" value="200"/>	<input type="button" value="ON"/>
Maximum velocity:	<input type="text" value="50"/>	<input type="button" value="Read from RAM"/>	<input type="text" value="HW: 7, SW:3.58.00 RC39 PV"/>
Maximum acceleration:	<input type="text" value="90"/>	<input type="button" value="Read from FLASH"/>	<input type="button" value="Enable"/>
Change of acceleration:	<input type="text" value="1"/>	<input type="button" value="Save to RAM"/>	<input type="button" value="Disable"/>
Maximum deceleration:	<input type="text" value="90"/>	<input type="button" value="Save to FLASH"/>	<input type="button" value="Override Limits"/>
Change of deceleration:	<input type="text" value="1"/>	<input type="button" value="Refresh"/>	<input type="button" value="Restore Limits"/>
Minimum position:	<input type="text" value="-221"/>	<input type="button" value="Restore Axis Settings"/>	<input type="text" value="SUCCESS"/>
Maximum position:	<input type="text" value="126"/>	<input type="button" value="RESET HEAD"/>	<input type="button" value="Home Zero"/>
Backlash Offset:	<input type="text" value="0"/>		<input type="button" value="Direct Zero"/>
Goto Style:	<input type="text" value="All Axes"/>		<input type="text" value="-101.237236"/>
Home style:	<input type="text" value="OPTO VANE"/>		<input type="text" value="-"/>
Home velocity:	<input type="text" value="3.12"/>		<input type="text" value="+"/>
Home time:	<input type="text" value="60"/>		<input type="text" value="-101.237236"/>
Home offset:	<input type="text" value="0"/> <input type="button" value="Copy Current"/>		<input type="text" value="VELOCITY MODE"/>
Restriction Type:	<input type="text" value="Controller"/>		<input type="text" value="STOP"/>
Automatic Homing:	<input type="text" value="No"/>		
Override motor:	<input type="text" value="Yes"/>		
Signal Gain:	<input type="text" value="30"/>		
Tacho Gain:	<input type="text" value="30"/>		
Integral Gain:	<input type="text" value="20"/>		
Current Limit (mA):	<input type="text" value="500"/>		
Temperature Limit:	<input type="text" value="180"/>		
Positional Error Limit:	<input type="text" value="250"/>		
Stepper Pulse Length:	<input type="text" value="6"/>		
PWM Type:	<input type="text" value="Unipolar"/>		
Homing Current:	<input type="text" value="32223"/>		
PV Filter:	<input type="text" value="0.99"/>		

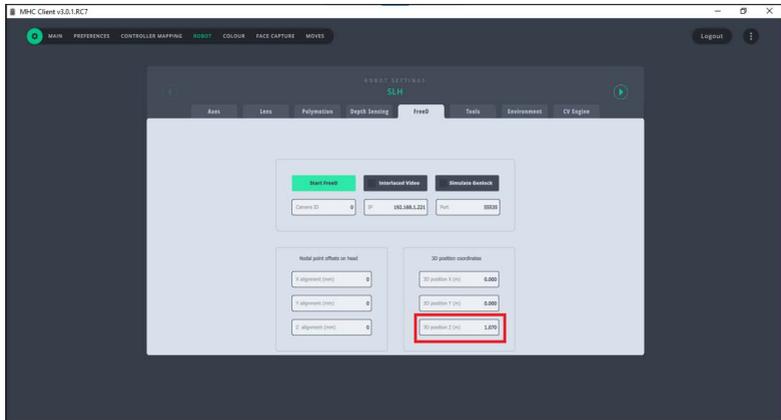
To test scaling factor correctness move the column to 100mm. The current position should be changed to 100 units.

- Run SLH to it Zero position (using MHC). Use the following diagram to measure SLH Z Room offset in metres using a tape

measure and add it in the **3D Position Z (m)** box for SLH's FreeD tab.



Z Room Offsets



Setting up offsets on PTA-2

1. Ensure you got correct scaling factors on the PAN and TILT Axis.
Use the following MHC Server Axis Settings screens for reference:

PAN

Axis Settings
✕

<p>Motor type: <input type="text" value="CAN"/></p> <p>Scaling: <input type="text" value="-1.71661e-06"/></p> <p>Maximum velocity: <input type="text" value="10"/></p> <p>Maximum acceleration: <input type="text" value="90"/></p> <p>Change of acceleration: <input type="text" value="1"/></p> <p>Maximum deceleration: <input type="text" value="90"/></p> <p>Change of deceleration: <input type="text" value="1"/></p> <p>Minimum position: <input type="text" value="-180"/></p> <p>Maximum position: <input type="text" value="180"/></p> <p>Backlash Offset: <input type="text" value="0"/></p> <p>Goto Style: <input type="text" value="All Axes"/></p> <p>Home style: <input type="text" value="ABS CAN"/></p> <p>Home velocity: <input type="text" value="-0"/></p> <p>Home time: <input type="text" value="0"/></p> <p>Home offset: <input type="text" value="-0"/> <input type="button" value="Copy Current"/></p> <p>Restriction Type: <input type="text" value="Controller"/></p> <p>Automatic Homing: <input type="text" value="No"/></p> <p>Override motor: <input type="text" value="Yes"/></p> <p>Signal Gain: <input type="text" value="0"/></p> <p>Tacho Gain: <input type="text" value="0"/></p> <p>Integral Gain: <input type="text" value="0"/></p> <p>Current Limit (mA): <input type="text" value="1000"/></p> <p>Temperature Limit: <input type="text" value="0"/></p> <p>Positional Error Limit: <input type="text" value="250"/></p> <p>Stepper Pulse Length: <input type="text" value="250"/></p> <p>PWM Type: <input type="text" value="Unipolar"/></p> <p>Homing Current: <input type="text" value="275"/></p> <p>PV Filter: <input type="text" value="0.85"/></p>	<p><input type="button" value="Read 2"/></p> <p><input type="text" value="Pan"/></p> <p><input type="button" value="Read from RAM"/></p> <p><input type="button" value="Read from FLASH"/></p> <p><input type="button" value="Save to RAM"/></p> <p><input type="button" value="Save to FLASH"/></p> <p><input type="button" value="Refresh"/></p> <p><input type="button" value="Restore Axis Settings"/></p> <p><input type="button" value="RESET HEAD"/></p>	<p><input type="button" value="Connected"/></p> <p><input type="button" value="ON"/></p> <p>HW: 1, SW: 1.14.00 RC33 PV</p> <p><input type="button" value="Enable"/></p> <p><input type="button" value="Disable"/></p> <p><input type="button" value="Override Limits"/></p> <p><input type="button" value="Restore Limits"/></p> <p><input type="button" value="SUCCESS"/></p> <p><input type="button" value="Home Zero"/></p> <p><input type="button" value="Direct Zero"/></p> <p><input type="text" value="-90.375504"/></p> <p><input type="button" value="-"/> <input style="margin-left: 20px;" type="button" value="+"/></p> <p><input type="text" value="-90.375504"/></p> <p><input type="button" value="VELOCITY MODE"/></p> <p><input style="width: 100%;" type="button" value="STOP"/></p>
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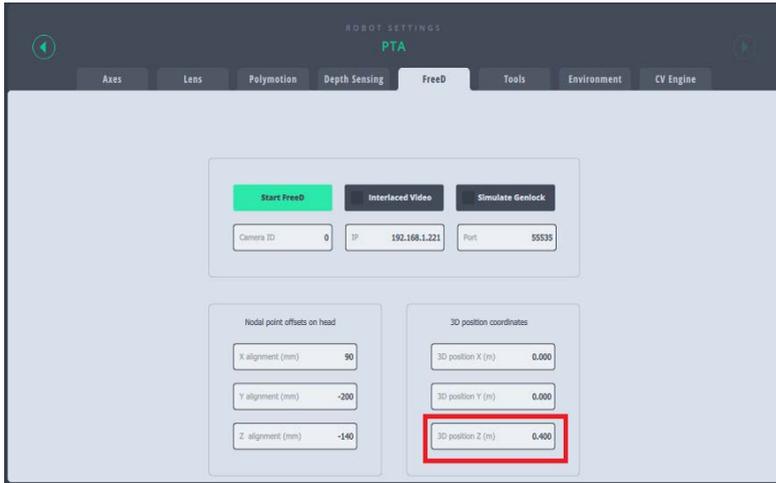
TILT

Axis Settings
✕

<p>Motor type: <input type="text" value="CAN"/></p> <p>Scaling: <input type="text" value="1.71661e-06"/></p> <p>Maximum velocity: <input type="text" value="90"/></p> <p>Maximum acceleration: <input type="text" value="90"/></p> <p>Change of acceleration: <input type="text" value="1"/></p> <p>Maximum deceleration: <input type="text" value="90"/></p> <p>Change of deceleration: <input type="text" value="1"/></p> <p>Minimum position: <input type="text" value="-24"/></p> <p>Maximum position: <input type="text" value="90"/></p> <p>Backlash Offset: <input type="text" value="0"/></p> <p>Goto Style: <input type="text" value="All Axes"/></p> <p>Home style: <input type="text" value="ABS CAN"/></p> <p>Home velocity: <input type="text" value="0"/></p> <p>Home time: <input type="text" value="0"/></p> <p>Home offset: <input type="text" value="0"/> <input type="button" value="Copy Current"/></p> <p>Restriction Type: <input type="text" value="Controller"/></p> <p>Automatic Homing: <input type="text" value="No"/></p> <p>Override motor: <input type="text" value="Yes"/></p> <p>Signal Gain: <input type="text" value="0"/></p> <p>Tacho Gain: <input type="text" value="0"/></p> <p>Integral Gain: <input type="text" value="0"/></p> <p>Current Limit (mA): <input type="text" value="1000"/></p> <p>Temperature Limit: <input type="text" value="0"/></p> <p>Positional Error Limit: <input type="text" value="250"/></p> <p>Stepper Pulse Length: <input type="text" value="250"/></p> <p>PWM Type: <input type="text" value="Unipolar"/></p> <p>Homing Current: <input type="text" value="275"/></p> <p>PV Filter: <input type="text" value="0.85"/></p>	<p>Head 2 <input type="text" value="Head 2"/></p> <p><input type="text" value="TILT"/></p> <p><input type="button" value="Read from RAM"/></p> <p><input type="button" value="Read from FLASH"/></p> <p><input type="button" value="Save to RAM"/></p> <p><input type="button" value="Save to FLASH"/></p> <p><input type="button" value="Refresh"/></p> <p><input type="button" value="Restore Axis Settings"/></p> <p><input type="button" value="RESET HEAD"/></p>	<p><input type="button" value="Connected"/></p> <p><input type="button" value="ON"/></p> <p>HW: 1, SW: 1.14.00 RC33 PV</p> <p><input type="button" value="Enable"/></p> <p><input type="button" value="Disable"/></p> <p><input type="button" value="Override Limits"/></p> <p><input type="button" value="Restore Limits"/></p> <p><input type="button" value="SUCCESS"/></p> <p><input type="button" value="Home Zero"/></p> <p><input type="button" value="Direct Zero"/></p> <p><input type="text" value="-17.946238"/></p> <p><input type="button" value="-"/> <input style="margin-left: 20px;" type="button" value="+"/></p> <p><input type="text" value="-17.946238"/></p> <p><input type="button" value="VELOCITY MODE"/></p> <p><input style="width: 100%;" type="button" value="STOP"/></p>
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Setting up Z Room Offset on PTA-2

Switch to the PTA head FreeD settings in MHC. Use the above 'Z Room Offsets' diagram to measure the PTA Z Room Offset and enter the value (in metres) in the **3D Position Z (m)** box for the PTA.

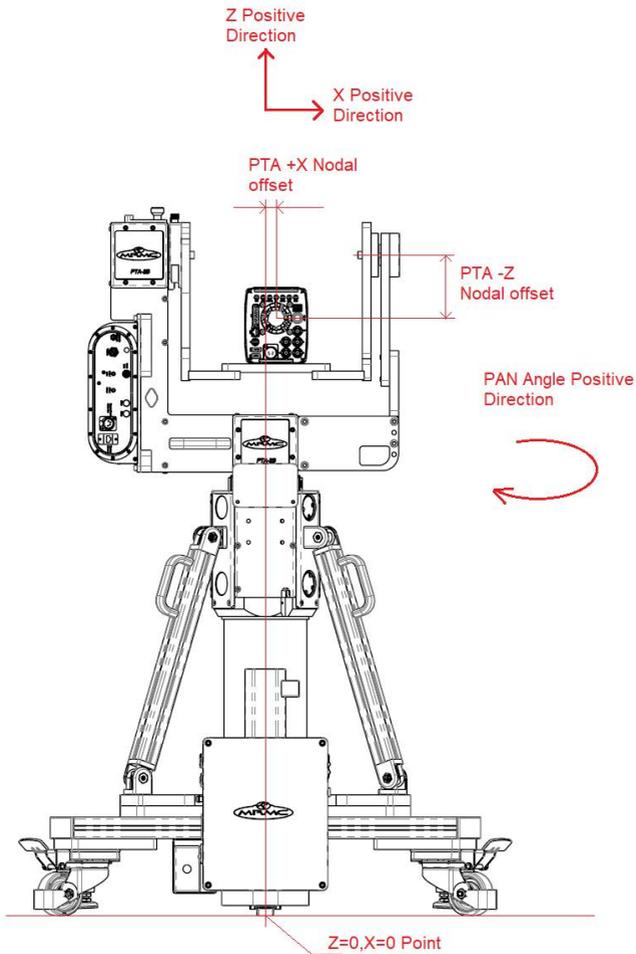


Setting up X, Y and Z nodal offset on PTA-2

Note

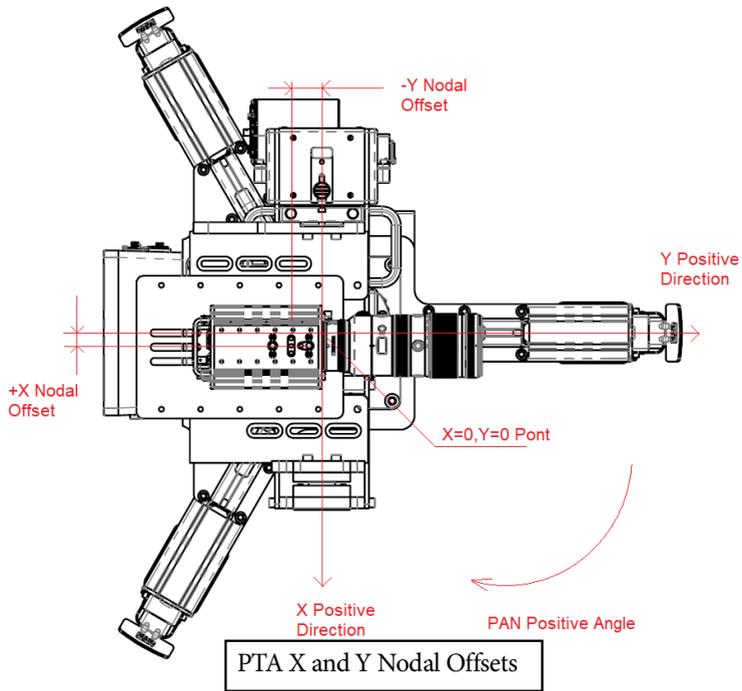
The X, Y and Z Nodal offsets are to be measured with respect to the camera sensor.

Use the following drawing to measure the X and Z Nodal offsets on the PTA-2 head. Note that the positive Z direction is upwards and positive X is on the right.

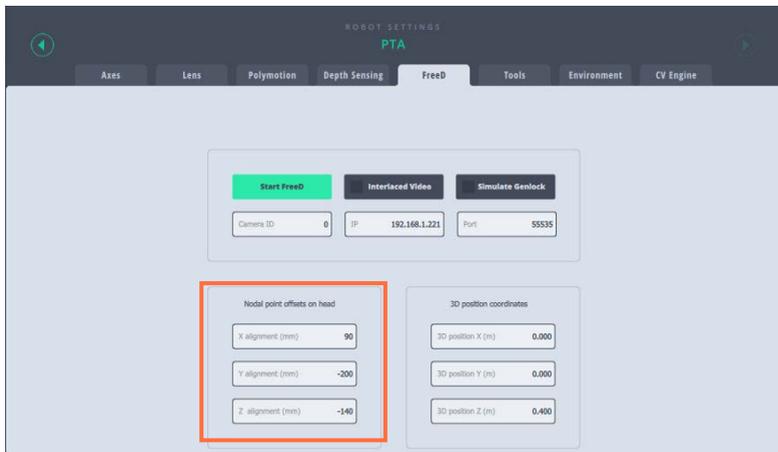


PTA X and Z Nodal Offsets

Use the following drawing to measure the Y Nodal offsets on the PTA-2 head. Note the positivity of Y direction.



Following is an example of the PTA Nodal offsets in MHC.



PTA Nodal Offsets in MHC

Advanced FreeD Box's screen overview

Button	Function
1	Toggle between the screens on the FreeD box display
2	Save settings
3	Start/stop the FreeD box
4	Not used



FreeD box Screen 1



FreeD box Screen 2



FreeD box Screen 3

Screen showing below can be useful to doublecheck that system is setup properly and running.

SRC1 Freq. indicates that FreeD Source 1 (which is the head) is transmitting FreeD packets with a indicated frequency. It also means that the head is receiving sync signal on its genlock input. (Assuming sync simulation is turned off).

SRC2 Freq. indicates that FreeD Source 2 (which is the SLH column) is transmitting FreeD packets with a indicated frequency. It also means that SLH is receiving sync signal on its genlock input. (Assuming sync simulation is turned off).

Sync Freq. is a test feature that can be used to check if sync signal is present in the coax sync cable plugged into advanced sync box. Note that Advanced sync box does not require sync signal supplied to it.



FreeD box Screen 4



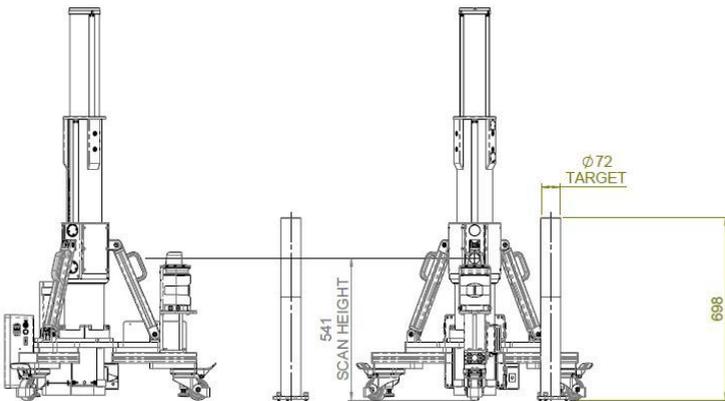
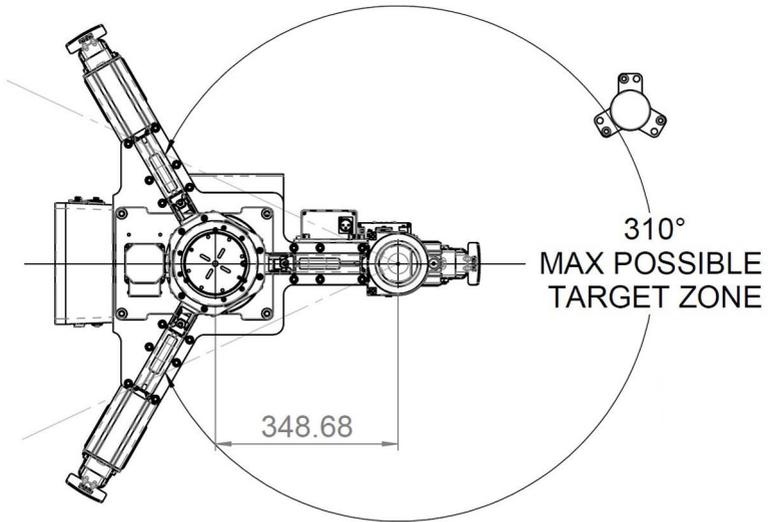
FreeD box Screen 5

After the entire system is setup properly in that user interface is used to run or stop 2D scanner in order to get positional data for the SLH+PTA-2 system. After positional data have been acquired (may take 10s to settle) button SAVE can be used to save current position. That position will be saved and system position will be known even after power off/on cycle. If SLH was moved while 2D scanner was off it will be required to run scanner again to update (and SAVE) new current position.

Notes

Appendix 1 Specifications

Electrical connection	24V, Ethernet, provided by the SLH control box
Host control	Embedded device, for example a modified FreeD box. Only for offline mapping and target management: A Windows PC/Laptop with SICK software.
Command interface	SICK Protocol to scanner itself, other commands internal to MRMC. Offline Mapping and target management using SICK “SOPAS” engineering tool – this tool is not required in normal operation.
Scanner Position accuracy:	+/-10mm
Scanner angular accuracy	+/- 0.1 degree
Maximum weight	Mounts on SLH (adds about 10kg)
Temperature range	Studio use
IP Rating	Indoor use



Notes

Notes

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