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C#	1

List Motion

× ListMotion

Code

C#

```
private void btnTest_Click(object sender, EventArgs e)
{
    //
    // 가
    // )
    //
    //
    // 8 (0~7)

    // 0~31 Mask,
    // 1,2,3 axisMask1 = 14
    uint axisMask1 = 0;

    // 32~63 Mask,
    uint axisMask2 = 0;
    int speedMode = (int)ec.EEcmSpeedMode.ecmSMODE_TRAPE;
    int stepID = 0;
    if (axisList.Count() < 31)
    {
        axisMask1 = (uint)(1 << axisID);
        axisMask2 = 0;
    }
    else
    {
        axisMask1 = 0;
        axisMask2 = (uint)(0x01 << (axisID - 32));
    }

    lmMapIndex = 0;

    double initSpeed = 0;
    double endSpeed = 0;
    double workSpeed = 0;
    double accel = 0;
    double decel = 0;

    //
    // , ecmLmCtl_Run()

    ec.ecmLmCtl_Begin(netID, lmMapIndex, axisMask1, axisMask2, ref
```

```

errorCode);

    // lmMapIndex
    ec.ecmLmCtl_ClearQue(netID, lmMapIndex, ref errorCode);
    // 가
    initSpeed = 0;
    endSpeed = 20000;
    accel = 10000;
    decel = 0; // decel = 0
    workSpeed = endSpeed; // workSpeed endSpeed
    ec.ecmSxCfg_SetSpeedPatt(netID, axisID, speedMode, initSpeed,
endSpeed, workSpeed, accel, decel, ref errorCode);
    // ID
    ec.ecmLmCfg_SetStepId(netID, lmMapIndex, stepID++, ref errorCode);

    //
    ec.ecmSxMot_MoveStart(netID, axisID, 20000, ref errorCode);
    // 가
    initSpeed = endSpeed; //
endSpeed가 InitSpeed가
    endSpeed = 40000; //
    accel = 20000;
    decel = 0;
    workSpeed = endSpeed; // workSpeed endSpeed
    ec.ecmSxCfg_SetSpeedPatt(netID, axisID, speedMode, initSpeed,
endSpeed, workSpeed, accel, decel, ref errorCode);

    //
    ec.ecmLmCfg_SetStepId(netID, lmMapIndex, stepID++, ref errorCode);
    ec.ecmSxMot_MoveStart(netID, axisID, 50000, ref errorCode);

    // 가 ,
    initSpeed = endSpeed; //
endSpeed가 InitSpeed가
    endSpeed = 40000; //
    accel = 10000;
    decel = 10000;
    workSpeed = 50000;
    ec.ecmSxCfg_SetSpeedPatt(netID, axisID, speedMode, initSpeed,
endSpeed, workSpeed, accel, decel, ref errorCode);

    //
    ec.ecmLmCfg_SetStepId(netID, lmMapIndex, stepID++, ref errorCode);
    ec.ecmSxMot_MoveStart(netID, axisID, 100000, ref errorCode);

    // 가 ,
    initSpeed = endSpeed; //
endSpeed가 InitSpeed가
    endSpeed = 20000; //
    accel = 0; // 가 accel = 0
    decel = 20000;
    workSpeed = initSpeed; // , workSpeed

```

```

        , workSpeed = initSpeed 가
        ec.ecmSxCfg_SetSpeedPatt(netID, axisID, speedMode, initSpeed,
endSpeed, workSpeed, accel, decel, ref errorCode);

//
    ec.ecmLmCfg_SetStepId(netID, lmMapIndex, stepID++, ref errorCode);
    ec.ecmSxMot_MoveStart(netID, axisID, 70000, ref errorCode);

//
    initSpeed = endSpeed; //
endSpeed가 InitSpeed가
    endSpeed = 0; //
    accel = 0; // 가          accel = 0
    decel = 10000;
    workSpeed = initSpeed;
    ec.ecmSxCfg_SetSpeedPatt(netID, axisID, speedMode, initSpeed,
endSpeed, workSpeed, accel, decel, ref errorCode);

//
    ec.ecmLmCfg_SetStepId(netID, lmMapIndex, stepID, ref errorCode);
    ec.ecmSxMot_MoveStart(netID, axisID, 20000, ref errorCode);
//
    ec.ecmLmCtl_Run(netID, lmMapIndex, ref errorCode);
    int runStepCount = 0, runStepID = 0, runStepState = 0;

    int timeLimit = 100000;
    Stopwatch sw = new Stopwatch();
    sw.Start();
    bool isSuccess = false;

//          timeLimit
    Task.Factory.StartNew(() =>
    {
        while (sw.ElapsedMilliseconds < timeLimit)
        {
            //
                ec.ecmLmSt_GetRunStepInfo(netID, lmMapIndex, ref
runStepCount, ref runStepID, ref runStepState, ref errorCode);

                // runStepID :          StepID
                // runStepState :          Step          (Ready, Busy,
Paused, Completed)

                //          StepID가          StepID          ,          가
Complete

                // StepCount          ecmLmSt_GetRemStepCount
RemStep

                if (runStepID == stepID && runStepState ==
(int)ec.EEcmLmCmdItemSts.ecmLM_CMDITEM_STS_COMPLETED)
                {
                    isSuccess = true;
                    break;

```

```
        }

        lblRunStepCount.BeginInvoke(new Action(() =>
lblRunStepCount.Text = runStepCount.ToString()));
        lblRunStepID.BeginInvoke(new Action(() =>
lblRunStepID.Text = runStepID.ToString()));
        lblRunStepState.BeginInvoke(new Action(() =>
lblRunStepState.Text =
((ec.EEcmLmCmdItemSts)runStepState).ToString()));
        Thread.Sleep(10);
    }

    if (!isSuccess)
    {
        //
    }
    //
    ec.ecmLmCtl_End(netID, lmMapIndex, ref errorCode);
});

if (!isSuccess)
{
    //
}
}
```

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