

File Machine View Help



Manual Control [F3] MDI [F5]

Axis: G X G Y G Z

Continuous

Home All Touch Off

Tool Touch Off

Preview DRO

```

X: 0.0000 DTG X: 0.0000
Y: 0.0000 DTG Y: 0.0000
Z: 0.0000 DTG Z: 0.0000
G54 X: 0.0000 G92 X: 0.0000
G54 Y: 0.0000 G92 Y: 0.0000
G54 Z: 0.0000 G92 Z: 0.0000
G54 R: 0.0000
TLO X: 0.0000
TLO Y: 0.0000
TLO Z: 0.0000
Vel: 0.0000
    
```

Feed Override: 100%

Rapid Override: 100%

Jog Speed: 15 in/min

Max Velocity: 60 in/min

Active G-Codes:

G80 G17 G40 G20 G90 G94 G54 G49 G99 G64  
G97 G91.1 G8 G92.2 M5 M9 M48 M53 M0 F0

```

1: ( AXIS "splash G-code" Not intended for
2: ( To run this code anyway you might have
3: ( depending on your setup. As if you had
4: ( Hint jog the Z axis down a bit then t
5: ( Also press the Toggle Skip Lines with
6: ( If the program is too big or small fo
7: ( LinuxCNC 19/1/2012 2:13:51 PM )
8: #<depth>=2.0
9: #<scale>=1.0
    
```

hm2/hm2\_7192.0: Data transmission not complete on channel hm2\_7192.0.ssi.00 read. You may need to change the timing of the hm2dpll timer. This warning will not repeat

Unexpected realtime delay on task 0 with period 1000000  
This Message will only display once per session.  
Run the Latency Test and resolve before continuing.

File Tree View Watch

Filter tree

Components Pins

- axis
- axisui
- halui
- hm2\_7192
  - 0
  - 7i70
  - dpll
    - 01
    - 02
    - 03
    - 04
  - base-freq-khz
  - ddsize
  - phase-error-us
  - plimit
  - prescale
  - time-const
- gpio
- led
- packet-error
- packet-error-exceeded
- packet-error-level
- read-request
- read
- sserial
- ssi
  - 00
    - data-invalid
    - xpositol
      - count
      - index-enable
      - position
      - rawcounts
      - reset
    - watchdog
    - write
- ini
- iocontrol
- joint
- motion-command-handler
- motion-controller
- motion

SHOW WATCH SETTINGS

Owner	Type	Dir	Value	Name
	bit	OUT	TRUE	hm2_7192.0.ssi.00.data-invalid
	s32	OUT	0	hm2_7192.0.ssi.00.xpositol.count
	bit	I/O	FALSE	hm2_7192.0.ssi.00.xpositol.index-enable
	float	OUT	0	hm2_7192.0.ssi.00.xpositol.position
	s32	OUT	0	hm2_7192.0.ssi.00.xpositol.rawcounts
	bit	I/O	FALSE	hm2_7192.0.ssi.00.xpositol.reset

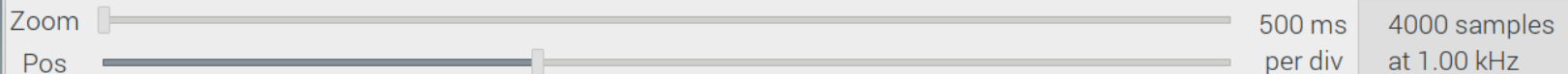
HAL command :  Execute

Commands may be tested here but they will NOT be saved

ESTOP No tool Position: Relative Actual

File Help

Horizontal



TRIGGER?

Run Mode

- Normal  
 Single  
 Roll  
 Stop

Trigger

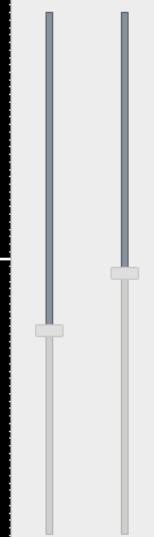
- Normal  
 Auto

Force

Level Pos

Vertical

Gain Pos

Scale  
500 /divLevel  
---Offset  
0.000

Rising

Chan Off

Source

None

 hm2\_7i92.0.dpll.phase-er  
 500 /div

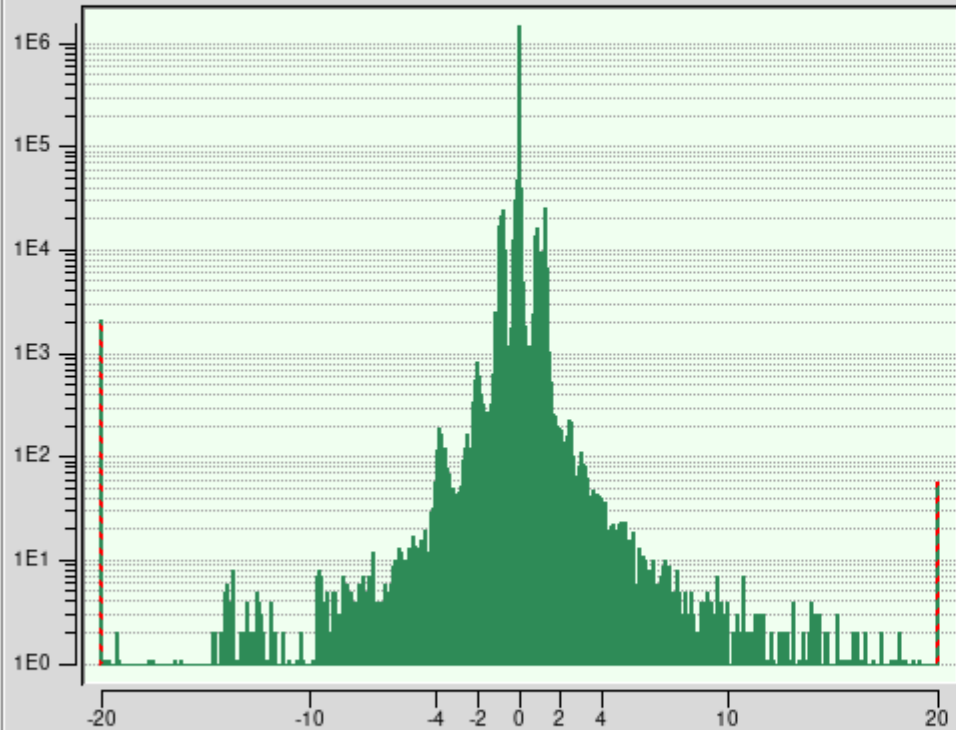
1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16
---	---	---	---	---	---	---	---	---	----	----	----	----	----	----	----

Selected Channel

1	hm2_7i92.0.dpll.phase-error-us	$f(-0.76600) = -260.69964$ (ddt -466750.10445)
---	--------------------------------	--

26Aug2023 raspberrypi linuxcnc  
aarch64 5.15.65-rt49-v8+ 2.9.0~pre0 DISPLAY=:0  
4 cores isolcpus=1,2,3

Latency (μs) base thread (25.0 μs period, binsize=0.1 μs)

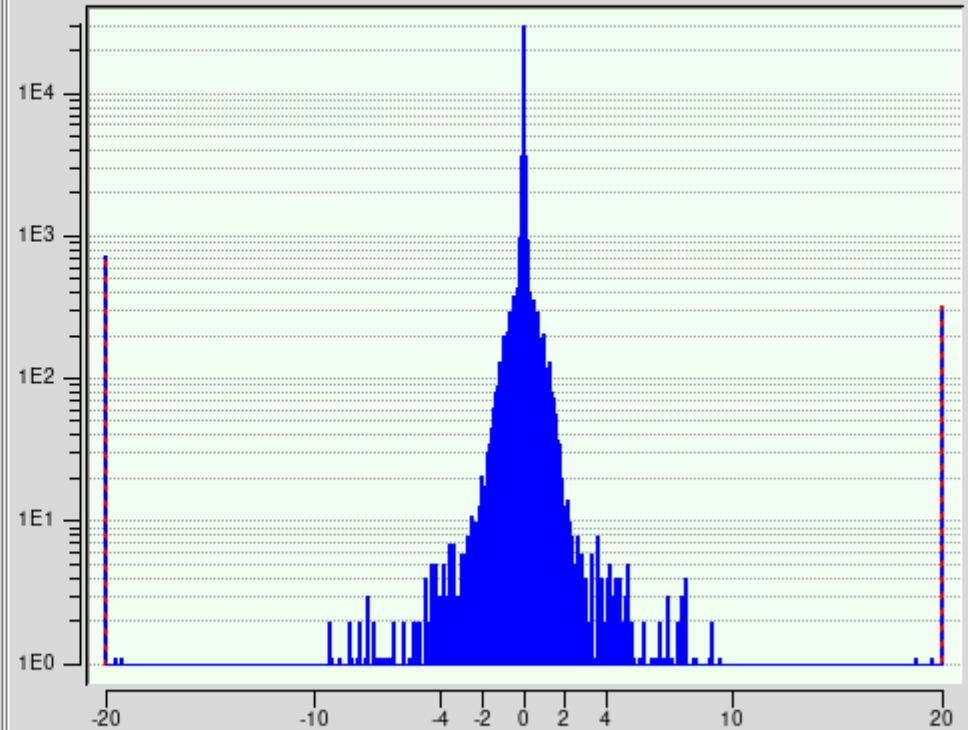


min (μs)  sdev (μs)  max (μs)

Display +/- bins:  2  4  10  20  40  100  200

Reset  ylogscale

Latency (μs) servo thread (1000.0 μs period, binsize=0.1 μs)

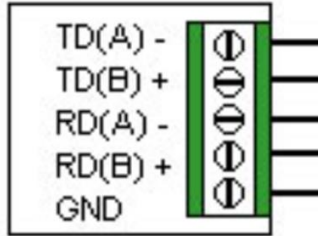


min (μs)  sdev (μs)  max (μs)

Display +/- bins:  2  4  10  20  40  100  200

Elapsed Time:

## 4-wire RS485 Master



PCW



Away

Replied by [PCW](#) on topic [SSI absolute encoders](#)

TXA = 1 = Orange/White = SSI Clock *Clock -*  
TXB = 2 = Orange = SSI /Clock *Clock +*  
RXA = 3 = Green/White = SSI Data *Data -*  
RXB = 6 = Green = SSI /Data *Data +*

5V and 5V sense to RJ45 7,8 (Brown,Brown/White)  
0V and 0V sense to RJ45 4,5 (Blue,Blue/White)  
( EIA/TIA 568B Colors )

## Encoder

### Connection Plan

SIGNAL

GND

Preset

Config

Data+

Data-

Clock-

Clock+

Power Supply