

What is NXTMMX

NXTMMX is a multiplexer to control additional NXT Motors from your NXT.



Connections and Placement

NXTMMX can be connected to any of the four sensor ports of NXT by using standard cables from NXT set, or FlexiCable from mindsensors.com.

Connect your motors to ports specified as M1 and M2.

Connect NXT to port specified as 'NXT'.

Additional Digital Sensors (or another NXTMMX) can be connected to port specified as 'Sensor'.



NOTE

Port specified as 'Sensor' on NXTMMX only supports I2C or Digital sensors or multiplexers.

Supplying power to your NXTMMX

The NXTMMX has Green terminals to connect external battery.



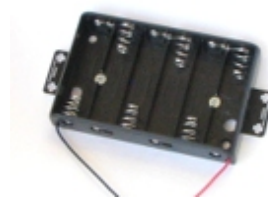
NOTE

NXTMMX is rated for external power supply of 10 volts DC max. Ensure to not exceed this value. While connecting external battery, ensure correct polarity.

Recommended Battery Options

6AA batteries (rechargeable or non-rechargeable).

To hold and mount these batteries, you can purchase a holder with NXT mounts as shown here from Mindsensors.com website.



7.2Volts or 9.6Volts Ni-CD or Ni-MH RC rechargeable battery. You can buy such battery and it's charger in local toy store.



Mounting NXTMMX on your contraption

The holes on the NXTMMX enclosure are designed for tight fit of Technic pins (or axles) with '+' cross section. The holes however are not designed for repeated insertions/removals of these pins.



To mount NXTMMX on your contraption we suggest that you use two dark gray 'Technic Axle 3 with Stud' as shown.

Insert axles from the top of the device and secure with a bushing on the back or mount it on your contraption directly.

Alternately, you may use blue 'Technic Axle Pin with Friction', as shown.



While disassembling contraption, leave the pins on the device.

Feature Highlights

Table below lists the important features provided by the NXTMMX. To use these features in your specific programming environment, please read your API help file (or NXT-G block help file) or program header file.

Feature	Description
Timed Control of each motor	Each motor can be run for a specified duration of time.
Encoder control of each motor	Each motor can be run from its current Encoder position to a new position (with or without a specific speed).
Speed control of each motor	Speed of each motor can be controlled in timed run or encoder based run.
Brake Vs Float while stopping the motors	Each motor can be set to Brake (where motor shaft can not be turned easily), Vs Float (where motor shaft is free to rotate by external force).
Holding Encoder position	At the end of run, hold the encoder position (i.e. motor turned by external force is restored to last set encoder position).
Turning motor by degrees	Move it in forward or reverse direction.
Turning motor by rotations	360 degrees makes one rotation.
Running operations asynchronously	While a motor is running other operations may be performed.

Feature	Description
Running motors for unlimited duration.	While motors are running, you can also perform other operations. NOTE: When motors are set to run for 'Unlimited Duration', they will continue to run until a Stop command is issued (or power is disconnected). In other words, after starting the motors for 'Unlimited Duration' if your program exits without stopping the motors, they will continue to run.
Stopping motors abruptly.	
Reading Motor Encoders	You can read the value of each encoder from the NXTMMX.

Programming Techniques for NXTMMX

NXT-G Method:

Please download custom NXT block from following URL and import it into your NXT-G IDE.

http://www.mindsensors.com/index.php?module=documents&JAS_DocumentManager_op=viewDocument&JAS_Document_id=156



Also download sample programs and modify them to suit your needs.

RobotC Method:

Download the library file from following URL, and at the top of your RobotC program file, include it with following directive:

```
#include "NXTMMX-lib.h"
```

Download library file and sample program from following URL:

http://www.mindsensors.com/index.php?module=documents&JAS_DocumentManager_op=viewDocument&JAS_Document_id=163

Also, ensure to download the help file, **NXTMMX-README-RobotC-api.html**, this file explains various functions available for your program.

Xander's RobotC Driver Suite:

Driver suite V1.4 or higher has built in support for NXTMMX.

Please refer to following SourceForge URL for details:

<http://rdpartyrobotcdr.sourceforge.net/>

NXC Method:

Download the library file from following URL, and at the top of your NXC program file, include it with following directive:

```
#include "NXTMMX-lib.nxc"
```

Library file URL:

http://www.mindsensors.com/index.php?module=documents&JAS_DocumentManager_op=viewDocument&JAS_Document_id=154

Ensure to download the help file, **NXTMMX-README-nxc-api.html**, this file explains various functions available for your program. You can also download sample program from this location, and modify it to meet your needs.

NXT Firmware

If you are programming in NXT-G or NXC, it is recommended to use firmware available at URL below. This firmware implements digital communication enhancements that will improve reliability of communication between NXT and attached sensors/multiplexers.

http://www.mindsensors.com/index.php?module=pagemaster&PAGE_user_op=view_page&PAGE_id=137

Current Characteristics

Average current consumption of this device is about 5.0 mA. NXTMMX can deliver upto 1 Amp current per NXT Motor attached. Drawing of excessively large current (such as incorrect motors or stalled motors) will result in internal shutdown until the situation is corrected.

I2C Bus address

Factory Default Address: 0x06

Changing the I2C Bus Address:

The I2C bus address of NXTMMX can be changed. To set an address different from default address, send sequence of following commands on the command register:

0xA0, 0xAA, 0xA5, <new I2C address>

Note: Send these commands with no break/read operation in between. This new address is effective immediately. Please note down your address carefully for future reference.

You can download the address change and scan functions from our website at www.mindsensors.com. These functions are written in RobotC.

Alternately, you can download NXT executable programs from following location: http://www.mindsensors.com/index.php?module=documents&JAS_DocumentManager_op=viewDocument&JAS_Document_id=91

APPENDIX A - Advanced Information

I2C Registers:

The NXTMMX appears as a set of registers as follows:

Register	Read	Write
0x00-0x07	Firmware version - <i>Vxxxx</i>	-
0x08-0x0f	Vendor Id - <i>mndsnsrs</i>	-
0x10-0x17	Device ID - NxTMMX	-
0x41	You can read the NXTMMX battery voltage at this register.	Command
Motor 1 Write Parameters		
0x42	Encoder Target for Motor 1 (long) 0x42: Least Significant Byte 0x43: Byte 2 0x44: Byte 3 0x45: Most Significant Byte	Encoder Target of Motor 1 (long)
0x46	Speed for Motor 1 (byte)	Speed for Motor 1 (byte)
0x47	Time to run in seconds for Motor 1 (byte)	Time to run in seconds for Motor 1 (byte)
0x48	Command register B for Motor 1	Command register B for Motor 1 (set this value to 0 as this is for future use)
0x49	Command register A for Motor 1 (read the description below for details of this register).	Command register A for Motor 1 (read the description below for details of this register).
Motor 2 Write Parameters		
0x4A	Encoder target for Motor 2 (long) 0x4A: Least Significant Byte 0x4B: Byte 2 0x4C: Byte 3 0x4D: Most Significant Byte	Encoder Value of Motor 2 (long)
0x4E	Speed for Motor 2 (byte)	Speed for Motor 2 (byte)
0x4F	Time to run in seconds for Motor 2 (byte)	Time to run in seconds for Motor 2 (byte)
0x50	Command register B for Motor 2	Command register B for Motor 2

0x51	Command register A for Motor 2 (read the description below for details of this register).	Command register A for Motor 2 (read the description below for details of this register).
Motor Read Parameters		
0x62	Encoder position of Motor 1 (long) 0x62: Least Significant Byte 0x63: Byte 2 0x64: Byte 3 0x65: Most Significant byte	-
0x66	Encoder position of Motor 2 (long) 0x66: Least Significant Byte 0x67: Byte 2 0x68: Byte 3 0x69: Most Significant Byte	-
0x72	Status Motor 1 (byte). See section below for details of this register.	
0x73	Status Motor 2 (byte). See section below for details of this register.	
0x76	Tasks Running for Motor 1 (byte)	
0x77	Tasks Running for Motor 2 (byte)	
	Registers for Advanced PID control	Writing these registers has immediate effect on operation. These registers will be reset to factory default values upon power cycle.
0x7A	Kp for Encoder Position Control (int) 0x7A: Least Significant Byte 0x7B: Most Significant Byte	Kp for Encoder Position Control (int)
0x7C	Ki for Encoder Position Control (int) 0x7C: Least Significant Byte 0x7D: Most Significant Byte	Ki for Encoder Position Control (int)
0x7E	Kd for Encoder Position Control (int) 0x7E: Least Significant Byte 0x7F: Most Significant Byte	Kd for Encoder Position Control (int)
0x80	Kp for Speed Control (int) 0x80: Least Significant Byte	Kp for Speed Control (int)

	0x81: Most Significant Byte	
0x82	Ki for Speed Control (int) 0x82: Least Significant Byte 0x83: Most Significant Byte	Ki for Speed Control (int)
0x84	Kd for Speed Control (int) 0x84: Least Significant Byte 0x85: Most Significant Byte	Kd for Speed Control (int)
0x86	Pass Count - The PID controller repeatedly reads internal encoder ticks, this is the number of times the encoder ticks reading should be within tolerance. (default 5)	Pass Count - Higher Pass count gives more time to position internal encoder, thus providing better accuracy in positioning, but will take longer time. Change this only if you need different motor positioning speeds and accuracy. (For normal usage, default values will be OK).
0x87	Tolerance - The Tolerance (in ticks) for encoder positioning. (default 80).	Tolerance - the accuracy you desire while positioning. Low number will position the encoders more accurately, but may take longer time. Change this only if you need different motor positioning speeds and accuracy. (For normal usage, default values will be OK).

Supported I2C Commands:

CMD	Hex	Description
R	0x52	Reset all Encoder values and motor parameters. (This does not reset the PID parameters).
S	0x53	Issue commands to both motors at the same time, for Synchronized starting of both motors.
		Motor Stopping Commands
a	0x61	Motor 1: Float while stopping.
b	0x62	Motor 2: Float while stopping.
c	0x63	Motor 1 and 2: Float while stopping.
A	0x41	Motor 1: Brake while stopping.
B	0x42	Motor 2: Brake while stopping.
C	0x43	Motor 1 & 2: Brake while stopping.
		Encoder Reset Commands
r	0x72	Motor 1: Reset Encoder to zero
s	0x73	Motor 2: Reset Encoder to zero

These commands are issued on command register (0x41).

Motor Command Register Explained

Each motor has two command registers (Register A and Register B). In current release Register B is reserved for future use and must be set to zero.

Bits in Register A should be set to 1 to avail functionality as described below.

Register Bit	Turn this bit to 1 for following functionality
Least significant bit (bit 0)	Speed control of your motor. The NXTMMX will honor speed values specified in the speed register for the respective motor.
Bit 1	Ramp the speed up or down. While starting the motor or changing speed, the NXTMMX will ramp up or ramp down the power to new value. If this bit is zero, the power changes are sudden, e.g. full power is applied to motors as they start.
Bit 2	Relative change based on encoder values. This is useful when Bit 3 is turned on, and in this case, the NXTMMX will make a relative movement from last seen Encoder position (it will add the new Encoder position to old position and move to that resulting position). Useful when turning by degrees or rotations. If this bit is 0, the Encoder positions are taken as absolute values.
Bit 3	Encoder control of your motor. The NXTMMX will honor Encoder values specified in Encoder position register for respective motor. If speed values are also specified, and speed bit is set on, motors will rotate to new encoder position with the specified speed.
Bit 4	Brake or Float at the completion of motor movement. If this bit is 1, motor will Brake at the completion, otherwise it will float.
Bit 5	Encoder active feedback. This bit is used when Encoder control is used. If this bit is set to 1 at the completion of motor movement, the NXTMMX will continue to hold the Encoder position (i.e. if motor is turned by external force, NXTMMX will try to restore it to last specified Encoder position). If this bit is zero, the motor may float.
Bit 6	Timed control of your motor. The NXTMMX will honor the time specified value in 'Time to run' register and run the motor for specified time. (If Time control

Register Bit	Turn this bit to 1 for following functionality
	bit as well as Encoder Control bit is on, the Timed control has precedence over encoder control).
Most significant bit (bit 7)	GO . When this bit is set to 1, all above bit values are brought into effect. This is useful to synchronized starting of both motors. As it takes some time to write each motor's register values. The I2C command 'S' can be used to change these bits to 1 for both motors at once.

Motor Status Register Explained

Each motor has one status register. Each bit in status register indicates various situations with the motor as explained below.

Register Bit	Value 1 indicates the situation is true
Least significant bit (bit 0)	Speed Control is ON . Motor is programmed to move at a fixed speed.
Bit 1	Motor is Ramping (up or down) . If the Power ramp is enabled, this bit is 1 while the motor is ramping (while changing its speed).
Bit 2	Motor is powered . (This may not mean motor is moving.)
Bit 3	Positional Control is ON . The motor is either moving towards desired encoder position or holding its position.
Bit 4	Motor is in Brake mode . (0 value of this bit means motor is floating).
Bit 5	Motor is overloaded . If the external load prevents motor from achieving desired speed, this bit is set to 1.
Bit 6	Motor is in timed mode . This bit is 1 while the motor is programmed to move for given duration.
Most significant bit (bit 7)	Motor is stalled . The external load caused the motor to stop moving.

Running Motors for Unlimited Duration

Not specifying Encoder Control or Timed Control bit will result in unlimited running of motor, (the speed control is honored if specified). To stop motors started with 'Unlimited Duration' use respective Stop command from the command set.



NOTE

When motors are set to run for 'Unlimited Duration', they will continue to run until a Stop command is issued (or power is disconnected). In other words, after starting the motors for 'Unlimited Duration' if your program exits without stopping the motors, they will continue to run.

How to detect if motor is moving or not moving:

In General:

Anytime when the 'Stalled' bit is 1, the motor is not moving.

Running in encoder mode:

During moving:

Position Control bit (bit 3) is 1

'Motor is Powered' bit (bit 2) is 1

Finished moving normally:

All bits are zero

Stopped due to stall:

Position Control bit (bit 3) is 1

'Motor is Powered' bit (bit 2) is 1

Stalled bit (bit 7) is 1

Running in timed mode:

During moving:

Timed Mode bit (bit 6) is 1

'Motor is Powered' bit (bit 2) is 1

Finished moving normally:

All bits are zero

Stopped due to stall (while time is not over):

Timed Mode bit (bit 6) is 1

'Motor is Powered' bit (bit 2) is 1

Stalled bit (bit 7) is 1

Stopped due to stall (after time is over):

All bits are zero.

Upgrading NXTMMX firmware:

The NXTMMX is shipped with latest stable firmware, if you need to change/upgrade the firmware, follow the procedure described at URL below. (Before you do this, you may need to get new firmware file from Mindsensors Technology team).

http://www.mindsensors.com/index.php?module=pagemaster&PAGE_user_op=view_page&PAGE_id=121

If the Firmware Upgrader doesn't detect your NXTMMX, try this:

When the firmware Upgrader is looking for device, attach the device, remove it momentarily and attach it again.

