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NATIONAL TRANSPORTATION COMMUNICATIONS FOR ITS PROTOCOL (NTCIP) OBJECT DEFINITIONS FOR ACTUATED TRAFFIC SIGNAL CONTROLLER UNITS

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NEMA Standards Publication TS 3.5-1996

NATIONAL TRANSPORTATION COMMUNICATIONS FOR ITS PROTOCOL (NTCIP) OBJECT DEFINITIONS FOR ACTUATED TRAFFIC SIGNAL CONTROLLER UNITS

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Foreword

This publication describes the objects used for managing actuated traffic signal controller units.

The text consists of mandatory requirements which are classified as NEMA Standard Publication and information that is in conformance with NEMA Authorized Engineering Information. Both are defined in the back of each NEMA Standard Publication.

User inputs are solicited by canvass on each NEMA standards proposal for Transportation Management and Associated Control Equipment. This procedure provides guidance before industry action. Every comment received is acknowledged and the action taken reported to the submitter. Comments should be submitted to:

Vice President, Engineering Department
National Electrical Manufacturers Association
1300 N.17th Street
Rosslyn, Virginia 22209

This standards publication was developed by the Transportation Management Systems and Associated Control Devices section of the National Electrical Manufacturers Association. Section approval of the standard does not necessarily imply that all section members voted for its approval or participated in its development. At the time it was approved, the Transportation Management Systems and Associated Control Devices section had the following members.

ADDCO Manufacturing Co.—St. Paul, MN
American Electronic Sign—Spokane, WA
Automatic Signal/Eagle Signal Corporation—Austin, TX
BI Tran Systems, Inc.—Sacramento, CA
Cylink Corporation—Sunnyvale, CA
Eberle Design, Inc.—Phoenix, AZ
Econolite Control Products, Inc.—Anaheim, CA
Fiberoptic Display Systems, Inc.—Smithfield, RI
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Information Station Specialists, Inc.—Zeeland, MI
Intersection Development Corp.—Fullerton, CA
ITS Product Group—Ormond Beach, FL
McCain Traffic Supply, Inc.—Vista, CA
P B Farradyne Inc.—Rockville, MD
Peek Traffic - Transyt Corp.—Tallahassee, FL
Rockwell Automation—Mayfield Heights, OH
Safetran Traffic Systems, Inc.—Colorado Springs, CO
Skyline Products, Inc.—Colorado Springs, CO
3M Intelligent Transportation Systems—St. Paul, MN
Traffic Sensor Corp.—Corona, CA
Viggen Corp.—McLean, VA
Vultron, Inc.—Rochester Hills, MI

The Joint AASHTO/ITE/NEMA Committee on the NTCIP has recommended this standards publication for adoption to both the American Association of State Highway and Transportation Officials (AASHTO) and the Institute of Transportation Engineers (ITE). After adoption is approved by AASHTO and ITE, future printings of this publication will have a Joint AASHTO/ITE/NEMA Standard cover, and will appear different from this publication. Unless noted, the content of the publications will be the same.

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Section 1
General

1.1 SCOPE

This publication defines objects which are specific to actuated signal controllers. It also defines standardized object groups which can be used for conformance statements.

1.2 REFERENCES

For approved errata sheets, contact:

NTCIP Coordinator
National Electrical Manufacturers Association
1300 North 17th Street, Suite 1847
Rosslyn, VA 22209-3801
email: ntcip@nema.org

1.2.1 Normative References

Information on proposed errata, which are under discussion by the relevant NTCIP Working Group, is available on the World Wide Web at http://www.ntcip.org.

The following standards (normative references) contain provisions which, through reference in this text, constitute provisions of this Standard. Other documents and standards (other references) are referenced in these documents, which might provide a complete understanding of the entire protocol and the relations between all parts of the protocol. At the time of publication, the editions indicated were valid. All standards are subject to revision, and parties to agreements based on this Standard are encouraged to investigate the possibility of applying the most recent editions of the standard listed below.

The following standards contain provisions which, through reference in this text, constitute provisions of this Standard. While end users of NTCIP do not need to obtain these documents, they do provide a complete understanding of the protocol. At the time of publication, the editions indicated were valid. All standards are subject to revision, and parties to agreements based on this Standard are encouraged to investigate the possibility of applying the most recent editions of the standards listed below.

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ISO/IEC 8824-1:1995	*Information Technology—Abstract Syntax Notation One (ASN.1): Specification of Basic Notation*
ISO/IEC 8824-2:1995	*Information Technology—Abstract Syntax Notation One (ASN.1): Information Object Specification*

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Electronic copies of RFC documents may be obtained using "anonymous FTP" to the host <nic.ddn.mil> or <ds.internic.net>. Printed copies are available from: (800) 365-3642 or (703) 802-4535.

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RFC1155 *Structure and Identification of Management Information for TCP/IP-based Internets.* K. McCloghrie; M. Rose; 05/10/1990

RFC1212 *Concise MIB Definitions.* K. McCloghrie; M. Rose; 03/26/1991

1.2.2 Other References

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1300 North 17th Street, Suite 1847
Rosslyn, VA 22209

TS 2-1992 *Traffic Controller Assemblies*

TS 3.1-1996 *National Transportation Communications for ITS Protocol - Overview*

TS 3.2-1996 *National Transportation Communications for ITS Protocol - Simple Transportation Management Framework*

TS 3.3-1996 *National Transportation Communications for ITS Protocol - Class B Profile*

ANSI
11 West 42nd Street, 13th Floor
New York, New York 10036
(212) 642-4900

ISO/IEC 8824-3:1995 *Information Technology—Abstract Syntax Notation One (ASN.1): Constraint Specification*

ISO/IEC 8824-4:1995 *Information Technology—Abstract Syntax Notation One (ASN.1): Parameterization of ASN.1 Specifications*

ISO/IEC 8825-1:1995 *Information Technology—ASN.1 Encoding Rules: Specification of Basic Encoding Rules (BER), Canonical Encoding Rules (CER) and Distinguished Encoding Rules (DER).*

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Chantilly, VA 22021

RFC1213 *Management Information Base for Network Management of TCP/IP-based Internets:* MIB-II. K. McCloghrie; M. Rose; CP/IP-base

RFC1157 *A Simple Network Management Protocol (SNMP).* M. Schoffstall; M. Feder; J. Davin; J. Case; 05/10/1990

1.3 ACTUATED CONTROLLER UNIT TERMS

These terms define the nomenclature frequently used in regard to actuated traffic signal control devices. These terms reflect the consensus of the traffic control equipment industry as represented by NEMA and are intended to be in harmony with terminology in current usage.

Actuation: The operation of any type of detector.

Automatic Flash: Automatic programmed flash mode not caused by manual switch activation or fault condition or startup.

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Auxiliary Function: A control that may activate auxiliary functions or outputs in an actuated controller unit.

Backup Mode: Control by local TBC or Interconnect based on absence of master or central command.

Barrier: A barrier (compatibility line) is a reference point in the preferred sequence of a multi-ring CU at which all rings are interlocked. Barriers assure there will be no concurrent selection and timing of conflicting phases for traffic movement in different rings. All rings cross the barrier simultaneously to select and time phases on the other side.

Call: A registration of a demand for right-of-way by traffic (vehicles or pedestrians) to a controller unit.

Call, Serviceable Conflicting: A call which:

a. Occurs on a conflicting phase not having the right-of-way at the time the call is placed.
b. Occurs on a conflicting phase which is capable of responding to a call.
c. When occurring on a conflicting phase operating in an occupancy mode, remains present until given its right-of-way.

Channel: Three circuits of a Monitor Device wired to monitor the green, yellow, and red outputs of the associated load switch position in the Terminal & Facilities. Channel 1 is assumed to monitor Load Switch 1, etc.

Check: An output from a controller unit that indicates the existence of unanswered call(s).

Concurrency Group: A group of phases which describes possible timing combinations. A phase within the group shall be able to time concurrently with any other phase from another ring contained in the group. For example, in the typical dual-ring eight phase design, phases 1, 2, 5 and 6 form one concurrency group and phases 3, 4, 7, and 8 form another concurrency group.

Concurrent Timing: A mode of controller unit operation whereby a traffic phase can be selected and timed simultaneously and independently with another traffic phase.

Controller Assembly: A complete electrical device mounted in a cabinet for controlling the operation of a traffic control signal display(s).

Controller Unit: A controller unit is that portion of a controller assembly that is devoted to the selection and timing of signal displays.

Coordination: The control of controller units in a manner to provide a relationship between specific green indications at adjacent intersections in accordance with a time schedule to permit continuous operation of groups of vehicles along the street at a planned speed.

Coordinator: A device or program/routine which provides coordination.

Cycle: The total time to complete one sequence of signalization around an intersection. In an actuated controller unit, a complete cycle is dependent on the presence of calls on all phases. In a pretimed controller unit it is a complete sequence of signal indications.

Cycle Length: The time period in seconds required for one complete cycle.

Detector, Pedestrian: A detector that is responsive to operation by or the presence of a pedestrian.

Detector, System: Any type of vehicle detector used to obtain representative traffic flow information.

Detector, Vehicle: A detector that is responsive to operation by or the presence of a vehicle.

Dial: The cycle timing reference or coordination input activating same. Dial is also frequently used to describe the cycle.

Display Map: A graphic display of the street system being controlled showing the status of the signal indications and the status of the traffic flow conditions.

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Dual Entry: Dual entry is a mode of operation (in a multi-ring CU) in which one phase in each ring must be in service. If a call does not exist in a ring when it crosses the barrier, a phase is selected in that ring to be activated by the CU in a predetermined manner.

Dwell: The interval portion of a phase when present timing requirements have been completed.

First Coordinated Phase: The coordinated phase which occurs first within the concurrent group of phases containing the coordinated phase(s) when there are constant calls on all phases.

Flash: Operation where one section in each vehicle signal (yellow or red) is alternately on and off with a one second cycle time and a 50 percent duty cycle.

Fault Monitor State: internal CU diagnostics have determined that the CU device is not in a safe operational state. An output may be asserted to indicate this condition.

Force Off: A command to force the termination of the green interval in the actuated mode or Walk Hold in the nonactuated mode of the associated phase. Termination is subject to the presence of a serviceable conflicting call. The Force Off function shall not be effective during the timing of the Initial, Walk, or Pedestrian Clearance. The Force Off shall only be effective as long as the condition is sustained. If a phase specific Force Off is applied, the Force Off shall not prevent the start of green for that phase.

Free: Operation without coordination control from any source.

Gap Reduction: A feature whereby the Unit Extension or allowed time spacing between successive vehicle actuations on the phase displaying the green in the extensible portion of the interval is reduced.

Group: Any portion of a traffic control network (system) that can be controlled by a common set of timing plans.

Hold: A command that retains the existing Green interval.

Hold-On Line: A signal to an intersection controller commanding it to remain under computer control.

Interconnect: A means of remotely controlling some or all of the functions of a traffic signal.

Intersection status: The knowledge of whether a controlled intersection is on-line and which mode it is currently operating in.

Interval: The part or parts of the signal cycle during which signal indications do not change.

Load Switch Driver Group: The set of three outputs which are used to drive load switch inputs to provide a Green, Yellow, or Red output condition for vehicle signals or Walk, Ped Clear, or Dont Walk output condition for pedestrian signals.

Malfunction Management Unit (MMU): A device used to detect and respond to improper and conflicting signals and improper operating voltages in a traffic controller assembly.

Maximum Green: The maximum green time with an serviceable opposing actuation, which may start during the initial portion.

Minimum Green Interval: The shortest green time of a phase. If a time setting control is designated as Minimum Green, the green time shall be not less than that setting.

Multi-Ring Controller Unit: A multi-ring CU contains two or more interlocked rings which are arranged to time in a preferred sequence and to allow concurrent timing of all rings, subject to barrier restraint.

Nonlocking Memory: A mode of actuated-controller-unit operation which does not require the retention of a call for future utilization by the controller assembly.

Occupancy: A measurement of vehicle presence within a zone of detection, expressed in seconds of time a given point or area is occupied by a vehicle.

Off-line: A controller assembly not under the control of the normal control source.

Offset: The time relationship, expressed in seconds, between the starting point of the first coordinated phase Green and a system reference point.

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Omit, Phase: A command that causes omission of a selected phase.

On-line: A controller assembly under the control of the normal control source.

Overlap: A Green indication that allows traffic movement during the green intervals of and clearance intervals between two or more phases.

Passage Time: The time allowed for a vehicle to travel at a selected speed from the detector to the stop line.

Pattern: A unique set of coordination parameters (cycle value, split values, offset value, and sequence).

Pedestrian Clearance Interval: The first clearance interval for the pedestrian signal following the pedestrian WALK indication.

Pedestrian Recycle: A method of placing a recurring demand for pedestrian service on the movement when that movement is not in its Walk interval.

Permissive: A time period, during which the CU is allowed to leave the coordinated phase(s) under coordination control to go to other phases.

Phase Sequence: A predetermined order in which the phases of a cycle occur.

Phase, Active: The indicated phase is currently timing. A phase is always active if it is Green or Yellow (Walk or Pedestrian Clear for Pedestrian Phases). It is also active if it is timing Red Clearance. It may be considered active during Red Dwell.

Phase, Conflicting: Conflicting phases are two or more traffic phases which will cause interfering traffic movements if operated concurrently.

Phase, Nonconflicting: Nonconflicting phases are two or more traffic phases which will not cause interfering traffic movements if operated concurrently.

Phase, Pedestrian: A traffic phase allocated to pedestrian traffic which may provide a right-of-way pedestrian indication either concurrently with one or more vehicular phases, or to the exclusion of all vehicular phases.

Phase, Traffic: Those green, change and clearance intervals in a cycle assigned to any independent movement(s) of traffic.

Phase, Vehicular: A vehicular phase is a phase which is allocated to vehicular traffic movement as timed by the controller unit.

Preemption: The transfer of the normal control of signals to a special signal control mode for the purpose of servicing railroad crossings, emergency vehicle passage, mass transit vehicle passage, and other special tasks, the control of which require terminating normal traffic control to provide the priority needs of the special task.

Preemptor: A device or program/routine which provides preemption.

Progression: The act of various controller units providing specific green indications in accordance with a time schedule to permit continuous operation of groups of vehicles along the street at a planned speed.

Red Clearance Interval: A clearance interval which may follow the yellow change interval during which both the terminating phase and the next phase display Red signal indications.

Red Revert: Provision within the controller unit to assure a minimum Red signal indication in a phase following the Yellow Change interval of that phase .

Rest: The interval portion of a phase when present timing requirements have been completed.

Ring: A ring consists of two or more sequentially timed and individually selected conflicting phases so arranged as to occur in an established order.

Sequence, Interval: The order of appearance of signal indications during successive intervals of a cycle.

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Single Entry: Single entry is a mode of operation (in a multi-ring CU) in which a phase in one ring can be selected and timed alone if there is no demand for service in a nonconflicting phase on the parallel ring(s).

Single-Ring Controller Unit: A single-ring CU contains two or more sequentially timed and individually selected conflicting phases so arranged as to occur in an established order.

Special Function: A control that may activate specific functions or outputs in an actuated controller unit.

Split: The segment of the cycle length allocated to each phase or interval that may occur (expressed in seconds). In an actuated controller unit, split is the time in the cycle allocated to a phase.

Standby Mode: An operational state called by master or central command which directs the controller unit to select Pattern, Automatic Flash, or Automatic Free based on local Time Base schedule or Interconnect inputs.

Time Base Control: A means for the automatic selection of modes of operation of traffic signals in a manner prescribed by a predetermined time schedule.

Timing Plan: The Split times for all segments (Phase/Interval) of the coordination cycle.

Volume: The number of vehicles passing a given point per unit of time.

Yellow Change Interval: The first interval following the green interval in which the signal indication for that phase is yellow.

Yield: A command which permits termination of the green interval.

1.4 ABBREVIATIONS AND ACRONYMS

The abbreviations used in this Standard Publication are defined as follows:

BIU—Bus Interface Unit

CA—Controller Assembly

CU—Controller Unit

MMU—Malfunction Management Unit

TBC—Time Base Control

TF—Terminals and Facilities

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Section 2
OBJECT DEFINITIONS

This section defines those objects which are specifically used by actuated traffic signal controllers. The objects are defined using the OBJECT-TYPE macro specified in RFC 1212. The text provided from Clause 2.1 through the end of the section (except the clause headings) constitutes the NEMA Standard ASC MIB.

The clauses below present the objects in lexigraphical order of their OBJECT IDENTIFIERS which correspond to their physical location within the global naming tree. All of the objects defined in this document reside under the "asc" node of the global naming tree. To aid in object management, the "asc" node has been subdivided into logical categories, each defined by a node under the "asc" node. The individual objects are then located under the appropriate node.

Nodes should not be confused with Conformance Groups, which are defined in Section 3. A Conformance Group is a logical grouping of objects which is used for conformance statements. While Conformance Groups will frequently correspond to the nodal structure, a Conformance Group may contain objects which are not lexigraphically ordered. For example, a Schedule Conformance Group may contain both "global" and "asc" specific objects.

Text preceded by a double hyphen in the MIB definitions represent normative text for this standard.

2.1 MIB HEADER

```
ASC_MIB1 DEFINITIONS::= BEGIN
-- the following OBJECT IDENTIFIERS are used in the ASC MIB:

IMPORTS
   devices
   FROM TMIB;

asc OBJECT IDENTIFIER::= { devices 1 }
```

2.2 PHASE PARAMETERS

```
phase OBJECT IDENTIFIER
::= { asc 1 }
```

-- This node shall contain objects that configure, monitor or control phase functions for this device.

2.2.1 Maximum Phases

```
maxPhases  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
             "The Maximum Number of Phases this Actuated Controller Unit supports. This object
             indicates the maximum rows which shall appear in the phaseTable object."
        ::= { phase 1 }
```

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2.2.2 Phase Table

```
phaseTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF PhaseEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit phase parameters. The number of rows in this
            table is equal to the maxPhases object."
::= { phase 2 }

phaseEntry  OBJECT-TYPE
        SYNTAX  PhaseEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit phase."
        INDEX  { phaseNumber }
::= { phaseTable 1 }

PhaseEntry ::= SEQUENCE {
        phaseNumber                 INTEGER,
        phaseWalk                   INTEGER,
        phasePedestrianClear        INTEGER,
        phaseMinimumGreen           INTEGER,
        phasePassage                INTEGER,
        phaseMaximum1               INTEGER,
        phaseMaximum2               INTEGER,
        phaseYellowChange           INTEGER,
        phaseRedClear               INTEGER,
        phaseRedRevert              INTEGER,
        phaseAddedInitial           INTEGER,
        phaseMaximumInitial         INTEGER,
        phaseTimeBeforeReduction    INTEGER,
        phaseCarsBeforeReduction    INTEGER,
        phaseTimeToReduce           INTEGER,
        phaseReduceBy               INTEGER,
        phaseMinimumGap             INTEGER,
        phaseDynamicMaxLimit        INTEGER,
        phaseDynamicMaxStep         INTEGER,
        phaseStartup                INTEGER,
        phaseOptions                INTEGER,
        phaseRing                   INTEGER,
        phaseConcurrency            OCTET STRING }
```

2.2.2.1 Phase Number

```
phaseNumber  OBJECT-TYPE
        SYNTAX  INTEGER (1..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The phase number for objects in this row. This value shall not exceed the maxPhases object
            value."
::= { phaseEntry 1 }
```

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2.2.2.2 Phase Walk Parameter

```
phaseWalk  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Walk Parameter in seconds. This shall control the amount of time the Walk indication
            shall be displayed."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.2.a"
::= { phaseEntry 2 }
```

2.2.2.3 Phase Pedestrian Clear Parameter

```
phasePedestrianClear  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Pedestrian Clear Parameter in seconds. This shall control the duration of the
            Pedestrian Clearance output (if present) and the flashing period of the Don't Walk output. "
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.2.b"
::= { phaseEntry 3 }
```

2.2.2.4 Phase Minimum Green Parameter

```
phaseMinimumGreen  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Minimum Green Parameter in seconds (NEMA TS 2 range: 1-255 sec). The first
            timed portion of the Green interval which may be set in consideration of the storage of
            vehicles between the zone of detection for the approach vehicle detector(s) and the stop
            line."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.a.(1)"
::= { phaseEntry 4 }
```

2.2.2.5 Phase Passage Parameter

```
phasePassage  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Passage Parameter in tenth seconds (0-25.5 sec). Passage Time, Vehicle Interval,
            Preset Gap, Vehicle Extension: the extensible portion of the Green shall be a function of
            vehicle actuations that occur during the Green interval. The phase shall remain in the
            extensible portion of the Green interval as long as the passage timer is not timed out. The
            timing of this portion of the green interval shall be reset with each subsequent vehicle
            actuation and shall not commence to time again until the vehicle actuation is removed."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.a.(2)"
::= { phaseEntry 5 }
```

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2.2.2.6 Phase Maximum Green 1 Parameter

```
phaseMaximum1  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Maximum 1 Parameter in seconds (NEMA TS 2 range: 1-255 sec). This time setting
            shall determine the maximum length of time this phase may be held Green in the presence
            of a serviceable conflicting call. In the absence of a serviceable conflicting call the Maximum
            Green timer shall be held reset unless Max Vehicle Recall is enabled for this phase. This is
            the default maximum value to use. It may be overridden via an external input,
            coordMaximumMode or other method."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1, 3.5.3.2.1.a.(3) and 3.5.3.5"
::= { phaseEntry 6 }
```

2.2.2.7 Phase Maximum Green 2 Parameter

```
phaseMaximum2  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Maximum 2 Parameter in seconds (NEMA TS 2 range: 1-255 sec). This time setting
            shall determine the maximum length of time this phase may be held Green in the presence
            of a serviceable conflicting call. In the absence of a serviceable conflicting call the Maximum
            Green timer shall be held reset unless Max Vehicle Recall is enabled for this phase. This
            may be implemented as the max green timer via an external input, coordMaximumMode or
            other method."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1, 3.5.3.2.1.a.(3), 3.5.3.5 and 3.5.4.1 (7)"
::= { phaseEntry 7 }
```

2.2.2.8 Phase Yellow Change Parameter

```
phaseYellowChange  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Yellow Change Parameter in tenth seconds (NEMA TS 2 range: 3-25.5 sec).
            Following the Green interval of each phase the CU shall provide a Yellow Change interval
            which is timed according to the Yellow Change parameter for that phase."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.5.a"
::= { phaseEntry 8 }
```

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2.2.2.9 Phase Red Clear Parameter

```
phaseRedClear  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Red Clearance Parameter in tenth seconds (0-25.5 sec). Following the Yellow
            Change interval for each phase, the CU shall provide a Red Clearance interval which is
            timed according to the Red Clearance parameter for that phase."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.5.b"
::= { phaseEntry 9 }
```

2.2.2.10 Phase Red Revert

```
phaseRedRevert OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Red revert time parameter in tenth seconds . A minimum Red indication to be timed
            following the Yellow Change interval and prior to the next display of Green on the same
            signal output driver group.
            The unitRedRevert parameter shall act as a minimum red revert time for all signal displays.
            The phaseRedRevert parameter may increase the red revert time for a specific phase. If the
            phaseRedRevert parameter is less than the unitRedRevert the unitRedRevert time shall be
            used."
::= { phaseEntry 10 }
```

2.2.2.11 Phase Added Initial Parameter

```
phaseAddedInitial  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Added Initial Parameter in tenths of seconds (0-25.5 sec). Added Initial parameter
            (Seconds / Actuation)  shall determine the time by which the variable initial time period will be
            increased from zero with each vehicle actuation received during the associated phase Yellow
            and Red intervals."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.b.(1).(b)"
::= { phaseEntry 11 }
```

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2.2.2.12 Phase Maximum Initial Parameter

```
phaseMaximumInitial  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Maximum Initial Parameter in seconds (0-255 sec). The maximum value of the
            variable initial timing period. Variable Initial timing shall equal the lesser of [added
            initial(seconds / actuation) * number of actuations] or [ Max Initial ]. The variable initial time
            shall not be less than Minimum Green."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.2.1.b.(1).(c)"
::= { phaseEntry 12 }
```

2.2.2.13 Phase Time Before Reduction Parameter

```
phaseTimeBeforeReduction  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Time Before Reduction (TBR) Parameter in seconds (0-255 sec). The Time Before
            Reduction period shall begin when the phase is Green and there is a serviceable conflicting
            call. If the serviceable conflicting call is removed before completion of this time (or time to
            reduce), the timer shall reset. Upon completion of the TBR period or the
            CarsBeforeReduction (CBR) parameter is satisfied, whichever occurs first, the linear
            reduction of the allowable gap from the Passage Time shall begin."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.b.(2)"
::= { phaseEntry 13 }
```

2.2.2.14 Phase Cars Before Reduction Parameter

```
phaseCarsBeforeReduction  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Phase Cars Before Reduction (CBR) Parameter (0-255 vehicles). When the phase is Green
            and the sum of the cars waiting (vehicle actuations during Yellow & Red intervals) on
            serviceable conflicting phases equals or exceeds the CBR parameter or the Time Before
            Reduction (TBR) parameter is satisfied, whichever occurs first, the linear reduction of the
            allowable gap from the Passage Time shall begin."
::= { phaseEntry 14 }
```

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2.2.2.15 Phase Time To Reduce Parameter

```
phaseTimeToReduce  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Time To Reduce Parameter in seconds (0-255 sec). This parameter shall control the
            rate of reduction of the allowable gap between the Passage Time and Minimum Gap setting."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.b.(2)"
::= { phaseEntry 15 }
```

2.2.2.16 Phase Reduce By

```
phaseReduceBy OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "This object may be used for volume density gap reduction as an alternate to the linear
            reduction defined by NEMA TS 1 and TS 2.  It contains the tenths of seconds to reduce the
            gap by (0.0 - 25.5  seconds).  The frequency of reduction shall produce the Minimum Gap
            after a time equal to the 'phaseTimeToReduce' object."
::= { phaseEntry 16 }
```

2.2.2.17 Phase Minimum Gap Parameter

```
phaseMinimumGap  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Phase Minimum Gap Parameter in tenth seconds (0-25.5 sec). The reduction of the
            allowable gap shall continue until the gap reaches a value equal to or less than the minimum
            gap as set on the Minimum Gap control after which the allowable gap shall remain fixed at
            the values set on the Minimum Gap control."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.1 and 3.5.3.2.1.b.(2)"
::= { phaseEntry 17 }
```

2.2.2.18 Phase Dynamic Max Limit

```
phaseDynamicMaxLimit  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "This object shall determine either the upper or lower limit of the running max in seconds (0-
            255) during dynamic max operation.
            The normal maximum (i.e. Max1, Max2, etc.) shall determine the other limit as follows:
                When dynamicMaxLimit is larger than the normal maximum, it shall become the upper
                limit.
                When dynamicMaxLimit is smaller than the normal maximum, it shall become the lower
                limit.
```

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Setting dynamicMaxLimit greater than zero enables dynamic max operation with the normal maximum used as the initial maximum setting. See dynamicMaxStep for details on dynamic max operation.
Maximum recall or a failed detector that is assigned to the associated phase shall disable dynamic max operation for the phase."
::= { phaseEntry 18 }

2.2.2.19 Phase Dynamic Max Step

phaseDynamicMaxStep OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS optional
DESCRIPTION
"This object shall determine the automatic adjustment to the running max in tenth seconds (0-25.5).
When a phase maxes out twice in a row, and on each successive max out thereafter, one dynamic max step value shall be added to the running max until such addition would mean the running max was greater than the larger of normal max or dynamic max limit.
When a phase gaps out twice in a row, and on each successive gap out thereafter, one dynamic max step value shall be subtracted from the running max until such subtraction would mean the running max was less than the smaller of the normal max or the dynamic max limit.
If a phase gaps out in one cycle and maxes out in the next cycle, or vice versa, the running max will not change."
::= { phaseEntry 19 }

2.2.2.20 Phase Startup

phaseStartup OBJECT-TYPE
SYNTAX INTEGER { other (1),
phaseNotOn (2),
greenWalk (3),
greenNoWalk (4),
yellowChange (5),
redClear (6) }
ACCESS read-write
STATUS mandatory
DESCRIPTION
"The Phase Startup parameter is an enumerated integer which selects the startup state for each phase after restoration of a defined power interruption or activation of the external start input. The following entries are defined:
other; this phase initializes in a state not defined by this standard.
phaseNotOn; this phase initializes in a Red state (the phase is not active and no intervals are timing).
greenWalk; this phase initializes at the beginning of the minimum green and walk timing intervals.
greenNoWalk; this phase initializes at the beginning of the minimum green timing interval.
yellowChange; this phase initializes at the beginning of the Yellow Change interval.
redClear; this phase initializes at the beginning of the Red Clearance interval."
REFERENCE
"NEMA TS 2 Clause 3.5.5.1 and 3.5.5.12"
::= { phaseEntry 20 }

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2.2.2.21 Phase Options

phaseOptions OBJECT-TYPE
SYNTAX INTEGER (0..65535)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Optional phase functions (0 = False/Disabled, 1 = True/Enabled)

Bit	Description
0	Enabled Phase - provide a means to define whether this phase is used in the current configuration. A disabled phase shall not provide any outputs nor respond to any phase inputs.
1	Automatic Flash Entry Phase - When Automatic Flash is called, the CU shall service the Entry Phase(s), clear to an All Red, then initiate flashing operation. Support is optional. REFERENCE NEMA TS 2 Clause 3.9.1.2.1
2	Automatic Flash Exit Phase - The CU shall move immediately to the beginning of the phase(s) programmed as Exit Phase(s) when Automatic Flash terminates. Support is optional REFERENCE NEMA TS 2 Clause 3.9.1.2.1
3	Non-Actuated 1 - when set to 1 causes a phase to respond to the Call To Non-Actuated 1 input (if present) or other method. Support is optional REFERENCE NEMA TS 2 Clause 3.5.5.5.8
4	Non-Actuated 2 - when set to 1 causes a phase to respond to the Call To Non-Actuated 2 input (if present) or other method. Support is optional REFERENCE NEMA TS 2 Clause 3.5.5.5.8
5	Non Lock Detector Memory - when set to 0 will cause the call to be locked at the beginning of the yellow interval. When set to 1 call locking will depend on the detectorOptions object. REFERENCE NEMA TS 2 Clause 3.5.3.4
6	Min. Vehicle Recall - when set to 1 causes recurring demand for vehicle service on the phase when that phase is not in its Green interval. REFERENCE NEMA TS 2 Clause 3.5.3.6
7	Max Vehicle Recall - when set to 1 causes a call on a phase such that the timing of the Green interval for that phase shall be extended to Maximum Green time. REFERENCE NEMA TS 2 Clause 3.5.3.5
8	Ped. Recall - when set to 1 causes a recurring pedestrian demand which shall function in the same manner as an external pedestrian call except that it shall not recycle the pedestrian service until a conflicting phase is serviced REFERENCE NEMA TS 2 Clause 3.5.3.7
9	Soft Vehicle Recall - when set to 1 causes a call on a phase when all conflicting phases are in green dwell or red dwell and there are no serviceable conflicting calls. Support is optional.
10	Dual Entry Phase - in multi-ring configurations when set to 1 causes the phase to become active upon entry into a concurrency group (crossing a barrier) when no calls exist in its ring within its concurrency group. REFERENCE NEMA TS 2 Clause 3.5.5.3
11	Simultaneous Gap Disable - in multi-ring configurations when set to 1 disables a gapped out phase from reverting to the extensible portion. Support is optional REFERENCE NEMA TS 2 Clause 3.5.5.3
12	Guaranteed Passage - when set to 1 enables an actuated phase operating in volume density mode (using gap reduction) to retain the right of way for the unexpired portion of the Passage time following the decision to terminate the green due to a reduced gap. Support is optional
13	Actuated Rest In Walk - when set to 1 causes an actuated phase to rest in Walk when there is no serviceable conflicting call at the end of Walk Timing.
14	Conditional Service Enable - in multi-ring configurations when set to 1 causes a gapped/maxed phase to conditionally service a preceding actuated vehicle phase when sufficient time remains before max time out of the phase(s) not prepared to terminate. Support is optional. REFERENCE NEMA TS 2 Clause 3.5.3.9

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15 AddedInitialCalculation - If set (1) the CU shall compare counts from all associated AddedInitial detectors and use the largest count value for the calculations. If clear (0) the CU shall sum all associated AddedInitial detector counts and use this sum for the calculations. The ability to modify the setting of this bit is optional."

::= { phaseEntry 21 }

2.2.2.22 Phase Ring Parameter

phaseRing OBJECT-TYPE
SYNTAX INTEGER (1..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Phase ring number (1..maxRings) that identified the ring which contains the associated phase. This value must not exceed the maxRings object value."
::= { phaseEntry 22 }

2.2.2.23 Phase Concurrency

phaseConcurrency OBJECT-TYPE
SYNTAX OCTET STRING
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Each octet contains a phase number (binary value) that may run concurrently with the associated phase. Phases that are contained in the same ring may NOT run concurrently."
::= { phaseEntry 23 }

2.2.3 Maximum Phase Groups

maxPhaseGroups OBJECT-TYPE
SYNTAX INTEGER (1..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The Maximum Number of Phase Groups (8 Phases per group) this Actuated Controller Unit supports. This value is equal to TRUNCATE [(maxPhases + 7) / 8]. This object indicates the maximum rows which shall appear in the phaseStatusGroupTable and phaseControlGroupTable."
::= { phase 3 }

2.2.4 Phase Status Group Table

phaseStatusGroupTable OBJECT-TYPE
SYNTAX SEQUENCE OF PhaseStatusGroupEntry
ACCESS not-accessible
STATUS mandatory
DESCRIPTION
"A table containing Actuated Controller Unit Phase Output (Red, Yellow, & Green) and Call (vehicle & pedestrian) status in groups of eight Phases. The number of rows in this table is equal to the maxPhaseGroups object."
::= { phase 4 }

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```
phaseStatusGroupEntry  OBJECT-TYPE
        SYNTAX  PhaseStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Red, Yellow, & Green Output Status and Vehicle and Pedestrian Call for eight Actuated
            Controller Unit Phases."
        INDEX  { phaseStatusGroupNumber }
::= { phaseStatusGroupTable 1 }

PhaseStatusGroupEntry ::= SEQUENCE {
        phaseStatusGroupNumber              INTEGER,
        phaseStatusGroupReds                INTEGER,
        phaseStatusGroupYellows             INTEGER,
        phaseStatusGroupGreens              INTEGER,
        phaseStatusGroupDontWalks           INTEGER,
        phaseStatusGroupPedClears           INTEGER,
        phaseStatusGroupWalks               INTEGER,
        phaseStatusGroupVehCalls            INTEGER,
        phaseStatusGroupPedCalls            INTEGER,
        phaseStatusGroupPhaseOns            INTEGER,
        phaseStatusGroupPhaseNexts          INTEGER }
```

2.2.4.1 Phase Status Group Number

```
phaseStatusGroupNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Phase StatusGroup number for objects in this row. This value shall not exceed the
            maxPhaseGroups object value."
::= { phaseStatusGroupEntry 1 }
```

2.2.4.2 Phase Status Group Reds

```
phaseStatusGroupReds  OBJECT-TYPE
    SYNTAX  INTEGER (0..255)
    ACCESS  read-only
    STATUS  mandatory
    DESCRIPTION
        "Phase Red Output Status Mask, when a bit = 1, the Phase Red is currently active. When a bit =
        0, the Phase Red is NOT currently active.
            Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
            Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
            Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
            Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
            Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
            Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
            Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
            Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 2 }
```

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2.2.4.3 Phase Status Group Yellows

```
phaseStatusGroupYellows  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Yellow Output Status Mask, when a bit = 1, the Phase Yellow is currently active.
            When a bit = 0, the Phase Yellow is NOT currently active.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 3 }
```

2.2.4.4 Phase Status Group Greens

```
phaseStatusGroupGreens  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Green Output Status Mask, when a bit = 1, the Phase Green is currently active.
            When a bit = 0, the Phase Green is NOT currently active.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 4 }
```

2.2.4.5 Phase Status Group Dont Walks

```
phaseStatusGroupDontWalks  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Dont Walk Output Status Mask, when a bit = 1, the Phase Dont Walk is currently
            active. When a bit = 0, the Phase Dont Walk is NOT currently active.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 5 }
```

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2.2.4.6 Phase Status Group Pedestrian clears

```
phaseStatusGroupPedClears  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Ped. Clear Output Status Mask, when a bit = 1, the Phase Ped. Clear is currently
            active. When a bit = 0, the Phase Ped. Clear is NOT currently active.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 6 }
```

2.2.4.7 Phase Status Group Walks

```
phaseStatusGroupWalks  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Walk Output Status Mask, when a bit = 1, the Phase Walk is currently active. When
            a bit = 0, the Phase Walk is NOT currently active.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 7 }
```

2.2.4.8 Phase Status Group Vehicle Calls

```
phaseStatusGroupVehCalls  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Phase Vehicle Call Status Mask, when a bit = 1, the Phase vehicle currently has a call for
            service. When a bit = 0, the Phase vehicle currently does NOT have a call for service.
                Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
                Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
                Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
                Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
                Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
                Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
                Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
                Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 8 }
```

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2.2.4.9 Phase Status Group Pedestrian Calls

phaseStatusGroupPedCalls OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Phase Pedestrian Call Status Mask, when a bit = 1, the Phase pedestrian currently has a call for service. When a bit = 0, the Phase pedestrian currently does NOT have a call for service.
Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 9 }

2.2.4.10 Phase Status Group Phase Ons

phaseStatusGroupPhaseOns OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Phase On Status Mask, when a bit = 1, the Phase is currently active. When a bit = 0, the Phase currently is NOT active. The phase is ON during the Green, Yellow, & Red Clearance intervals of that phase. It shall be permissible for this status to be True (bit=1) during the Red Dwell state.
Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 10 }

2.2.4.11 Phase Status Group Phase Nexts

phaseStatusGroupPhaseNexts OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Phase Next Status Mask, when a bit = 1, the Phase currently is committed to be NEXT in sequence & remains present until the phase becomes active (On/Timing). When a bit = 0, the Phase currently is NOT committed to be NEXT in sequence. The phase next to be serviced shall be determined at the end of the green interval of the terminating phase; except that if the decision cannot be made at the end of the Green interval, it shall not be made until after the end of all Vehicle Change & Clearance intervals.

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Bit 7 = Phase number = (phaseStatusGroupNumber * 8)
Bit 6 = Phase number = (phaseStatusGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseStatusGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseStatusGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseStatusGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseStatusGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseStatusGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseStatusGroupNumber * 8) - 7"
::= { phaseStatusGroupEntry 11 }

2.2.5 Phase Control Table

phaseControlGroupTable OBJECT-TYPE
SYNTAX SEQUENCE OF PhaseControlGroupEntry
ACCESS not-accessible
STATUS optional
DESCRIPTION
"A table containing Actuated Controller Unit Phase Control in groups of eight phases. The number of rows in this table is equal to the maxPhaseGroups object.
This table is optional for Actuated Controller Units conforming to this specification. If implemented then all objects in this table shall be implemented."
::= { phase 5 }

phaseControlGroupEntry OBJECT-TYPE
SYNTAX PhaseControlGroupEntry
ACCESS not-accessible
STATUS mandatory
DESCRIPTION
"Phase Control for eight Actuated Controller Unit phases."
INDEX { phaseControlGroupNumber }

::= { phaseControlGroupTable 1 }

PhaseControlGroupEntry ::= SEQUENCE {
phaseControlGroupNumber INTEGER,
phaseControlGroupPhaseOmit INTEGER,
phaseControlGroupPedOmit INTEGER,
phaseControlGroupHold INTEGER,
phaseControlGroupForceOff INTEGER,
phaseControlGroupVehCall INTEGER,
phaseControlGroupPedCall INTEGER }

2.2.5.1 Phase Control Group Number

phaseControlGroupNumber OBJECT-TYPE
SYNTAX INTEGER (1..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The Phase Control Group number for objects in this row. This value shall not exceed the maxPhaseGroups object value."
::= { phaseControlGroupEntry 1 }

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2.2.5.2 Phase Omit Control

phaseControlGroupPhaseOmit OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to omit phases from being serviced in the device. When a bit = 1, the device shall activate the System Phase Omit control for that phase. When a bit = 0, the device shall not activate the System Phase Omit control for that phase.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
REFERENCE
"NEMA TS 2 Clause 3.5.3.11.2"
::= { phaseControlGroupEntry 2 }

2.2.5.3 Pedestrian Omit Control

phaseControlGroupPedOmit OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to omit peds from being serviced in the device. When a bit = 1, the device shall activate the System Ped Omit control for that phase. When a bit = 0, the device shall not activate the System Ped Omit control for that phase.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
REFERENCE
"NEMA TS 2 Clause 3.5.3.11.3"
::= { phaseControlGroupEntry 3 }

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2.2.5.4 Phase Hold Control

phaseControlGroupHold OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to hold phases in the device. When a bit = 1, the device shall activate the System Phase Hold control for that phase. When a bit = 0, the device shall not activate the System Phase Hold control for that phase.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
REFERENCE
"NEMA TS 2 Clause 3.5.3.11.1"
::= { phaseControlGroupEntry 4 }

2.2.5.5 Phase Force Off Control

phaseControlGroupForceOff OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS optional
DESCRIPTION
"This object is used to apply force offs on a per phase basis. When a bit = 1, the device shall activate the System Phase Force Off control for that phase. When a bit = 0, the device shall not activate the System Phase Force Off control for that phase. When the phase green terminates, the associated bit shall be reset to 0.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
::= { phaseControlGroupEntry 5 }

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2.2.5.6 Vehicle Call Control

phaseControlGroupVehCall OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to place calls for vehicle service in the device. When a bit = 1, the device shall place a call for vehicle service on that phase. When a bit = 0, the device shall not place a call for vehicle service on that phase.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
::= { phaseControlGroupEntry 6 }

2.2.5.7 Pedestrian Call Control

phaseControlGroupPedCall OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to place calls for ped service in the device. When a bit = 1, the device shall place a call for ped service on that phase. When a bit = 0, the device shall not place a call for ped service on that phase.
Bit 7 = Phase number = (phaseControlGroupNumber * 8)
Bit 6 = Phase number = (phaseControlGroupNumber * 8) - 1
Bit 5 = Phase number = (phaseControlGroupNumber * 8) - 2
Bit 4 = Phase number = (phaseControlGroupNumber * 8) - 3
Bit 3 = Phase number = (phaseControlGroupNumber * 8) - 4
Bit 2 = Phase number = (phaseControlGroupNumber * 8) - 5
Bit 1 = Phase number = (phaseControlGroupNumber * 8) - 6
Bit 0 = Phase number = (phaseControlGroupNumber * 8) - 7

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the Backup timer to ZERO."
::= { phaseControlGroupEntry 7 }

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2.3 DETECTOR PARAMETERS

```
detector OBJECT IDENTIFIER
::= { asc 2 }

-- This defines a node for supporting detector objects.
```

2.3.1 Maximum Vehicle Detectors

```
maxVehicleDetectors OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Vehicle Detectors this Actuated Controller Unit supports. This
            object indicates the maximum rows which shall appear in the vehicleDetectorTable object."
::= { detector 1 }
```

2.3.2 Vehicle Detector Parameter Table

```
vehicleDetectorTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF VehicleDetectorEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit vehicle detector parameters. The number of
            rows in this table is equal to the maxVehicleDetectors object."
::= { detector 2 }

vehicleDetectorEntry  OBJECT-TYPE
        SYNTAX  VehicleDetectorEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit detector."
        INDEX  { vehicleDetectorNumber }
::= { vehicleDetectorTable 1 }

        VehicleDetectorEntry ::= SEQUENCE {
        vehicleDetectorNumber                   INTEGER ,
        vehicleDetectorOptions                  INTEGER ,
        vehicleDetectorCallPhase                INTEGER ,
        vehicleDetectorSwitchPhase              INTEGER ,
        vehicleDetectorDelay                    INTEGER ,
        vehicleDetectorExtend                   INTEGER ,
        vehicleDetectorQueueLimit               INTEGER ,
        vehicleDetectorNoActivity               INTEGER ,
        vehicleDetectorMaxPresence              INTEGER ,
        vehicleDetectorErraticCounts            INTEGER ,
        vehicleDetectorFailTime                 INTEGER ,
        vehicleDetectorAlarms                   INTEGER ,
        vehicleDetectorReportedAlarms           INTEGER ,
        vehicleDetectorReset                    INTEGER }
```

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2.3.2.1 Vehicle Detector Number

vehicleDetectorNumber OBJECT-TYPE
SYNTAX INTEGER (1..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The vehicle detector number for objects in this row. The value shall not exceed the maxVehicleDetectors object value."
::= { vehicleDetectorEntry 1 }

2.3.2.2 Vehicle Detector Options Parameter

vehicleDetectorOptions OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION

"Vehicle Detector Options Parameter as follows:

Bit	Function
7	Call - if set (1) the CU shall place a demand for vehicular service on the assigned phase when the phase is not timing the green interval.
6	Queue - if set (1) the CU shall extend the green interval of the assigned phase until a gap occurs (no actuation) or until the green has been active longer than the vehicleDetectorQueueLimit time. This is optional.
5	AddedInitial - if set (1) the CU shall accumulate detector actuation counts for use in the added initial calculations. Counts shall be accumulated from the beginning of the yellow interval to the beginning of the green interval.
4	Passage - if set (1) the CU shall maintain a reset to the associated phase passage timer for the duration of the detector actuation when the phase is green.
3	Red Lock Call - if set (1) the detector will lock a call to the assigned phase if an actuation occurs while the phase is not timing Green or Yellow. This mode is optional.
2	Yellow Lock Call - if set (1) the detector will lock a call to the assigned phase if an actuation occurs while the phase is not timing Green.
1	Occupancy Detector - if set (1) the detector collects data for the associated detector occupancy object(s). This capability may not be supported on all detector inputs to a device.
0	Volume Detector - if set (1) the detector collects data for the associated detector volume object(s). This capability may not be supported on all detector inputs to a device."

::= { vehicleDetectorEntry 2}

2.3.2.3 Vehicle Detector Call Phase Parameter

vehicleDetectorCallPhase OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object contains assigned phase number for the detector input associated with this row. The associated detector call capability is enabled when this object is set to a non-zero value. The value shall not exceed the value of maxPhases"
REFERENCE
"NEMA TS 2 Clause 3.5.5.5.4 and 3.5.5.5.5"
::= { vehicleDetectorEntry 4 }

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2.3.2.4 Vehicle Detector Switch Phase Parameter

```
vehicleDetectorSwitchPhase  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector Switch Phase Parameter (i.e., Phase Number). The phase to which a vehicle
            detector actuation shall be switched when the assigned phase is Yellow or Red and the
            Switch Phase is Green"
        REFERENCE
            "NEMA TS 2 Clause 3.5.5.5.4.c"
::= { vehicleDetectorEntry 5 }
```

2.3.2.5 Vehicle Detector Delay Parameter

```
vehicleDetectorDelay  OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector Delay Parameter in tenth seconds (0–255.0 sec). The period a detector actuation
            (input recognition) shall be delayed when the phase is not Green"
        REFERENCE
            "NEMA TS 2 Clause 3.5.5.5.4.a"
::= { vehicleDetectorEntry 6 }
```

2.3.2.6 Vehicle Detector Extend Parameter

```
vehicleDetectorExtend  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector Extend Parameter in tenth seconds (0–25.5 sec). The period a vehicle detector
            actuation (input duration) shall be extended from the point of termination , when the phase is
            Green"
        REFERENCE
            "NEMA TS 2 Clause 3.5.5.5.4.b"
::= { vehicleDetectorEntry 7 }
```

2.3.2.7 Vehicle Detector Queue Limit

```
vehicleDetectorQueueLimit  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Detector Queue Limit parameter in  seconds (0-255 sec).  The length of time that an
            actuation from a queue detector may continue into the phase green.  This time begins when
            the phase becomes green and when it expires any associated detector inputs shall be
            ignored.  This time may be shorter due to other overriding device parameters (i.e. Maximum
            time, Force Off's, ...)."
::= { vehicleDetectorEntry 8 }
```

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2.3.2.8 Vehicle Detector No Activity Parameter

```
vehicleDetectorNoActivity  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector No Activity diagnostic Parameter in minutes (0–255 min.) . If an active detector
            does not exhibit an actuation in the specified period, it is considered a fault by the diagnostics
            and the detector is classified as Failed. A value of 0 for this object shall disable this
            diagnostic for this detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.1"
::= { vehicleDetectorEntry 9 }
```

2.3.2.9 Vehicle Detector Maximum Presence Parameter

```
vehicleDetectorMaxPresence  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector Maximum Presence diagnostic Parameter in minutes (0-255 min.). If an active
            detector exhibits continuous detection for too long a period, it is considered a fault by the
            diagnostics and the detector is classified as Failed. A value of 0 for this object shall disable
            this diagnostic for this detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.2"
::= { vehicleDetectorEntry 10 }
```

2.3.2.10 Vehicle Detector Erratic Counts Parameter

```
vehicleDetectorErraticCounts  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Detector Erratic Counts diagnostic Parameter in counts/minute (0-255 cpm). If an active
            detector exhibits excessive actuations, it is considered a fault by the diagnostics and the
            detector is classified as Failed. A value of 0 for this object shall disable this diagnostic for this
            detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.3"
::= { vehicleDetectorEntry 11 }
```

2.3.2.11 Vehicle Detector Fail Time Parameter

```
vehicleDetectorFailTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Detector Fail Time in seconds (0..255). If a detector diagnostic indicates that the associated
            detector input is failed, then a call shall be placed on the associated phase during all non-
            green intervals.
            When each green interval begins the call shall be maintained for the length of time specified
            by this object and then removed.
```

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If the value of this object equals the maximum value (255) then a constant call shall be placed on the associated phase (max recall).

If the value of this object equals zero then no call shall be placed on the associated phase for any interval (no recall).

Compliant devices may support a limited capability for this object (i.e. only max recall or max recall and no recall). At a minimum the max recall setting must be supported."

::= { vehicleDetectorEntry 12 }

2.3.2.12 Vehicle Detector Alarms

vehicleDetectorAlarms OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"This object shall return indications of detector alarms. Detector Alarms are indicated as follows:

Bit	Definition
0	No Activity Fault: This detector has been flagged as non-operational due to lower than expected activity by the CU detector diagnostic.
1	Max Presence Fault: This detector has been flagged as non-operational due to a presence indicator that exceeded the maximum expected time by the CU detector diagnostic.
2	Erratic Output Fault: This detector has been flagged as non-operational due to erratic outputs (excessive counts) by the CU detector diagnostic.
3	Communications Fault: Communications to the device (if present) have failed.
4	Configuration Fault: Detector is assigned but is not supported.
5-6	Reserved.
7	Other Fault: The detector has failed due to some other cause.

Once set a bit shall maintain its state as long as the condition exists. The bit shall clear when the condition no longer exists."

::= { vehicleDetectorEntry 13 }

2.3.2.13 Vehicle Detector Reported Alarms

vehicleDetectorReportedAlarms OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS optional
DESCRIPTION
"This object shall return detector device reported alarms (via some communications mechanism). Inductive Loop Detector Alarms are indicated as follows:

Bit	Definition
0	Other
1	Watchdog Fault: This detector has been flagged as non-operational due to a watchdog error.
2	Open Loop Fault: This detector has been flagged as non-operational due to an open loop (broken wire).
3	Shorted Loop Fault: This detector has been flagged as non-operational due to a shorted loop wire.
4	Excessive Change Fault: This detector has been flagged as non-operational due to an inductance change that exceeded expected values.
5-7	Reserved

Once set a bit shall maintain its state as long as the condition exists. The bit shall clear when the condition no longer exists."

::= { vehicleDetectorEntry 14 }

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2.3.2.14 Vehicle Detector Reset

```
vehicleDetectorReset OBJECT-TYPE
        SYNTAX  INTEGER (0..1)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object when set to TRUE (non-zero) shall cause the CU to command the associated
            detector to reset. This object shall automatically return to FALSE (zero) after the CU has
            issued the reset command.

            NOTE: this may affect other detector (detector channels) that are physically attached to a
            common reset line."
::= { vehicleDetectorEntry 15 }
```

2.3.3 Maximum Vehicle Detector Status Groups

```
maxVehicleDetectorStatusGroups OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The maximum number of detector status groups (8 detectors per group) this device
            supports. This value is equal to TRUNCATE [(maxVehicleDetectors + 7 ) / 8]. This object
            indicates the maximum number of rows which shall appear in the
            vehicleDetectorStatusGroupTable object."
::= { detector 3 }
```

2.3.4 Vehicle Detector Status Group Table

```
vehicleDetectorStatusGroupTable OBJECT-TYPE
        SYNTAX  SEQUENCE OF VehicleDetectorStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing detector status in groups of eight detectors. The number of rows in this
            table is equal to the maxVehicleDetectorStatusGroups object."
::= { detector 4 }

vehicleDetectorStatusGroupEntry OBJECT-TYPE
        SYNTAX  VehicleDetectorStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A group (row) of detector status."
        INDEX  { vehicleDetectorNumber }
::= { vehicleDetectorStatusGroupTable  1 }

VehicleDetectorStatusGroupEntry ::= SEQUENCE {
        vehicleDetectorStatusGroupNumber        INTEGER ,
        vehicleDetectorStatusGroupActive        INTEGER ,
        vehicleDetectorStatusGroupAlarms        INTEGER  }
```

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2.3.4.1 Detector Status Group Number

vehicleDetectorStatusGroupNumber OBJECT-TYPE
SYNTAX INTEGER (1..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The detector status group number for objects in this row. This value shall not exceed the maxVehicleDetectorStatusGroups object value."
::= { vehicleDetectorStatusGroupEntry 1 }

2.3.4.2 Detector Status Group Active

vehicleDetectorStatusGroupActive OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"This object shall return the detection status of each detector associated with the group. Each detector shall be represented as ON (detect) or OFF (no-detect) by individual bits in this object. If a detector is ON then the associated bit shall be set (1). If a detector is OFF then the associated bit shall be clear (0).

Bit	Description
7	Detector number = (vehicleDetectorStatusGroupNumber * 8)
6	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 1
5	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 2
4	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 3
3	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 4
2	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 5
1	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 6
0	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 7"

::= { vehicleDetectorStatusGroupEntry 2 }

2.3.4.3 Detector Alarm Status

vehicleDetectorStatusGroupAlarms OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION

"This object shall return the alarm status of the detectors associated with the group. Each detector alarm status shall be represented as ON or OFF by individual bits in this object. If any detector alarm (defined in the vehicleDetectorAlarm object) is active the associated bit shall be set (1). If a detector alarm is not active the associated bit shall be clear (0).

Bit	Description
7	Detector number = (vehicleDetectorStatusGroupNumber * 8)
6	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 1
5	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 2
4	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 3
3	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 4
2	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 5
1	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 6
0	Detector number = (vehicleDetectorStatusGroupNumber * 8) - 7"

::= { vehicleDetectorStatusGroupEntry 3 }

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2.3.5 Volume / Occupancy report

volumeOccupancyReport OBJECT IDENTIFIER
::= { *detector* 5 }

-- This node contains the objects necessary to support volume / occupancy reporting .

2.3.5.1 Volume / Occupancy Sequence

volumeOccupancySequence OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION

"This object defines a Sequence Number for Volume / Occupancy data collection. This object is used to detect duplicate or missing reports. The value cycles within the limits of 0 to 255. This object is incremented by one at the expiration of the volumeOccupancyPeriod time."
::= { volumeOccupancyReport 1 }

2.3.5.2 Volume / Occupancy Period

volumeOccupancyPeriod OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object defines the number of seconds (0-255) that comprise the volume / occupancy collection period. When the collection period expires the device shall increment the volumeOccupancySequence, update the volumeOccupancyTable entries and reset the volume occupancy timer."
::= { volumeOccupancyReport 2 }

2.3.5.3 Active Volume / Occupancy Detectors

activeVolumeOccupancyDetectors OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The number of detectors in this device. This object indicates how many rows are in the volumeOccupancyTable object. There shall be a row for every detector that is collecting volume or occupancy data (refer to detectorOptions in the detectorTable)."
::= { volumeOccupancyReport 3 }

2.3.5.4 Volume / Occupancy Table

volumeOccupancyTable OBJECT-TYPE
SYNTAX SEQUENCE OF VolumeOccupancyEntry
ACCESS not-accessible
STATUS mandatory
DESCRIPTION
"A table containing Detector Volume and Occupancy data collected. The number of rows in this table is equal to the activeVolumeOccupancyDetectors object."
::= { volumeOccupancyReport 4 }

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```
volumeOccupancyEntry  OBJECT-TYPE
        SYNTAX  VolumeOccupancyEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "The Volume and Occupancy data collected for one of the detectors in the device."
        INDEX  { vehicleDetectorNumber }
::= { volumeOccupancyTable 1 }

VolumeOccupancyEntry ::=  SEQUENCE {
        detectorVolume      INTEGER,
        detectorOccupancy   INTEGER }
```

2.3.5.4.1 Volume data

```
detectorVolume  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Detector Volume data collected over the Volume / Occupancy Period. This value shall
            range from 0 to 254 indicating the volume of traffic crossing the associated detectorNumber
            during the collection period.

            The value 255 shall indicate volume overflow."
::= { volumeOccupancyEntry 1 }
```

2.3.5.4.2 Occupancy data

```
detectorOccupancy  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Detector Occupancy data collected over the Volume / Occupancy Period or Detector Unit
            Diagnostic Information. The value of the object shall indicate occupancy or detector
            diagnostic information as follows:
                Range       Meaning
                0-200       Detector Occupancy in 0.5% Increments
                201-209     Reserved
                210         Max Presence Fault
                211         No Activity Fault
                212         Open loop Fault
                213         Shorted loop Fault
                214         Excessive Change Fault
                215         Reserved
                216         Watchdog Fault
                217         Erratic Output Fault
                218-255     Reserved

            Faults shall be indicated for all collection periods during which a fault is detected if either
            occupancy data or volume data is being collected. The highest numbered fault shall be
            presented if more than one fault is active (i.e. indicate OpenLoop rather than NoActivity)."
::= { volumeOccupancyEntry 2 }
```

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2.3.6 Maximum Pedestrian Detectors

```
maxPedestrianDetectors OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Pedestrian Detectors this Actuated Controller Unit supports. This
            object indicates the maximum rows which shall appear in the pedestrianDetectorTable
            object."
::= { detector 6 }
```

2.3.7 Pedestrian Detector Parameter Table

```
pedestrianDetectorTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF PedestrianDetectorEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit pedestrian detector parameters. The number of
            rows in this table is equal to the maxPedestrianDetectors object."
::= { detector 7 }

pedestrianDetectorEntry  OBJECT-TYPE
        SYNTAX  PedestrianDetectorEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit pedestrian detector."
        INDEX  { pedestrianDetectorNumber }
::= { pedestrianDetectorTable 1 }

PedestrianDetectorEntry ::= SEQUENCE {
        pedestrianDetectorNumber        INTEGER,
        pedestrianDetectorCallPhase     INTEGER,
        pedestrianDetectorNoActivity    INTEGER,
        pedestrianDetectorMaxPresence   INTEGER,
        pedestrianDetectorErraticCounts INTEGER,
        pedestrianDetectorAlarms        INTEGER  }
```

2.3.7.1 Pedestrian Detector Number

```
pedestrianDetectorNumber  OBJECT-TYPE
        SYNTAX  INTEGER (1..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The pedestrianDetector number for objects in this row. The value shall not exceed the
            maxPedestrianDetectors object value."
::= { pedestrianDetectorEntry 1 }
```

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2.3.7.2 Pedestrian Detector Call Phase Parameter

```
pedestrianDetectorCallPhase  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object contains assigned phase number for the pedestrian detector input associated
            with this row. The associated detector call capability is enabled when this object is set to a
            non-zero value. The value shall not exceed the value of maxPhases."
::= { pedestrianDetectorEntry 2 }
```

2.3.7.3 Pedestrian Detector No Activity Parameter

```
pedestrianDetectorNoActivity  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Pedestrian Detector No Activity diagnostic Parameter in minutes (0–255 min.) . If an active
            detector does not exhibit an actuation in the specified period, it is considered a fault by the
            diagnostics and the detector is classified as Failed. A value of 0 for this object shall disable
            this diagnostic for this detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.1"
::= { pedestrianDetectorEntry 3 }
```

2.3.7.4 Pedestrian Detector Maximum Presence Parameter

```
pedestrianDetectorMaxPresence  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Pedestrian Detector Maximum Presence diagnostic Parameter in minutes (0-255 min.). If an
            active detector exhibits continuous detection for too long a period, it is considered a fault by
            the diagnostics and the detector is classified as Failed.  A value of 0 for this object shall
            disable this diagnostic for this detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.2"
::= { pedestrianDetectorEntry 4 }
```

2.3.7.5 Pedestrian Detector Erratic Counts Parameter

```
pedestrianDetectorErraticCounts  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Pedestrian Detector Erratic Counts diagnostic Parameter in counts/minute (0-255 cpm). If
            an active detector exhibits excessive actuations, it is considered a fault by the diagnostics
            and the detector is classified as Failed. A value of 0 for this object shall disable this
            diagnostic for this detector."
        REFERENCE
            "NEMA TS 2 Clause 3.9.3.1.4.3"
::= { pedestrianDetectorEntry 5 }
```

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2.3.7.6 Pedestrian Detector Alarms

pedestrianDetectorAlarms OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"This object shall return indications of detector alarms. Detector Alarms are indicated as follows:

Bit	Definition
0	No Activity Fault: This detector has been flagged as non-operational due to lower than expected activity by the CU detector diagnostic.
1	Max Presence Fault: This detector has been flagged as non-operational due to a presence indicator that exceeded the maximum expected time by the CU detector diagnostic.
2	Erratic Output Fault: This detector has been flagged as non-operational due to erratic outputs (excessive counts) by the CU detector diagnostic.
3	Communications Fault: Communications to the device (if present) have failed.
4	Configuration Fault: Detector is assigned but is not supported.
5-6	Reserved.
7	Other Fault: The detector has failed due to some other cause.

Once set a bit shall maintain its state as long as the condition exists. The bit shall clear when the condition no longer exists."
::= { pedestrianDetectorEntry 6 }

2.4 UNIT PARAMETERS

unit OBJECT IDENTIFIER
::= { asc 3 }
--"This defines a node for supporting unit objects."

2.4.1 StartUp Flash Parameter

unitStartUpFlash OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Unit Start up Flash time parameter in seconds (0 to 255 sec). The period/state (Start-Up Flash occurs when power is restored following a device defined power interruption. During the Start-Up Flash state, the Fault Monitor and Voltage Monitor outputs shall be inactive (if present)."
REFERENCE
"NEMA TS 2 Clause 3.9.1.1"
::= { unit 1 }

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2.4.2 Automatic Ped Clear Parameter

```
unitAutoPedestrianClear  OBJECT-TYPE
        SYNTAX  INTEGER {  disable(1),
                           enable (2) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Unit Automatic Ped Clear parameter (1 = False/Disable 2=True/Enable). When enabled, the
            CU shall time the Pedestrian Clearance interval when Manual Control Enable is active and
            prevent the Pedestrian Clearance interval from being terminated by the Interval Advance
            input."
        REFERENCE
            "NEMA TS 2 Clause 3.5.3.10"
::= { unit 2 }
```

2.4.3 Backup Time Parameter

```
unitBackupTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The Backup Time in seconds (0-65535). When one of the defined system control
            parameters is SET, the backup timer is reset and times the unitBackupTime interval.  If the
            unitBackupTime interval expires without a SET operation to one of the system control
            parameters, then the CU shall revert to Backup Mode.
            A value of zero (0) shall disable this feature.
            The system control parameters are:
            phaseControlGroupPhaseOmit, phaseControlGroupPedOmit, phaseControlGroupHold,
            phaseControlGroupForceOff, phaseControlGroupVehCall, phaseControlGroupPedCall,
            unitControl, systemPatternControl, systemSyncControl, preemptControlState,
            ringControlGroupStopTime, ringControlGroupForceOff, ringControlGroupMax2,
            ringControlGroupMaxInhibit, ringControlGroupPedRecycle, ringControlGroupRedRest,
            ringControlGroupOmitRedClear and unitControl."
::= { unit 3 }
```

2.4.4 Unit Red Revert Parameter

```
unitRedRevert  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The red revert in tenth seconds ( 0.0 - 25.5 seconds).  This value shall provide the minimum
            red revert time for all phases (i.e. if it is greater than a phaseRedRevert object value, then
            this value shall be used as the red revert time for the affected phase).
            This object provides a minimum Red indication following the Yellow Change interval and prior
            to the next display of Green on the same signal output driver group."
::= { unit 4 }
```

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2.4.5 Unit Control Status

```
unitControlStatus  OBJECT-TYPE
        SYNTAX  INTEGER {   other (1),
                            systemControl (2),
                            systemStandby (3),
                            backupMode(4),
                            manual (5),
                            timebase (6),
                            interconnect (7),
                            interconnectBackup (8)}
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Control Mode for Pattern, Flash, or Free at the device:
                systemControl;      control by master or central commands.
                systemStandby;      control by local based on master or central command to use local
                                    control.
                backupMode;         Backup Mode (see Terms).
                Manual;             control by entry other than zero in coordOperationalMode.
                timebase;           control by the local Time Base.
                interconnect;       control by the local Interconnect inputs.
                interconnectBackup; control by local TBC due to invalid Interconnect inputs or loss of sync.
                other;              control by a source other than those listed above.
            The value of this object is ignored when in BACKUP Mode.
            A write to this object shall reset the BACKUP timer to ZERO."
::= { unit 5 }
```

2.4.6 Unit Flash Status

```
unitFlashStatus  OBJECT-TYPE
        SYNTAX  INTEGER {   other(1),
                            notFlash(2),
                            automatic(3),
                            localManual(4),
                            faultMonitor(5),
                            mmu(6),
                            startup(7) ,
                            preempt (8)}.
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Flash modes:
                notFlash; the CU is not in Flash
                automatic; the CU is currently in an Automatic Flash state.
                localManual; the Controller Unit Local Flash input is active, MMU Flash input is not active,
                        and Flash is not commanded by the Master.
                faultMonitor; the CU is currently in a Fault Monitor State.
                mmu; the Controller Unit MMU Flash input is active and the CU is not in Start-Up Flash.
                startup; the CU is currently timing the Start-Up Flash period.
                preempt; the CU is currently timing the preempt Flash.
                other; the CU is in flash for some other reason."
::= { unit 6 }
```

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2.4.7 Unit Alarm Status 2

unitAlarmStatus2 OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Device Alarm Mask 2 (0 = False, 1 = True) as follows:
Bit 7 - Reserved.
Bit 6 - Reserved.
Bit 5 - Reserved.
Bit 4 - Stop Time - When either CU Stop Time Input becomes active.
Bit 3 - External Start - When the CU External Start becomes active.
Bit 2 - Response Fault - When any NEMA TS2 Port 1 response frame fault occurs.
Bit 1 - Low Battery - When any battery voltage falls below the required level.
Bit 0 - Power Restart - When power returns after a power interruption.
Once set, a bit shall maintain it's state as long as the condition exists."
::= { unit 7 }

2.4.8 Unit Alarm Status 1

unitAlarmStatus1 OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Device Alarm Mask 1 (0 = False, 1 = True) as follows:
Bit 7 - CoordActive - When coordination is active and not preempted or overridden.
Bit 6 - Local Free - When any of the Controller Unit inputs and/or programming cause it to not respond to coordination control.
Bit 5 - Local Flash - When the Controller Unit Local Flash input becomes active, MMU Flash input is not active, and Flash is not commanded by the system.
Bit 4 - MMU Flash - When the Controller Unit MMU Flash input remains active for a period of time exceeding the Start-Up Flash time.
Bit 3 - Cycle Fail - When a local Controller Unit is operating in the non-coordinated mode, whether the result of a Cycle Fault or Free being the current normal mode, and cycling diagnostics indicate that a serviceable call exists that has not been serviced for two cycles.
Bit 2 - Coord Fail - When a Coord Fault is in effect and a Cycle Fault occurs again within two cycles of the coordination retry.
Bit 1 - Coord Fault - When a Cycle Fault is in effect and the serviceable call has been serviced within two cycles after the Cycle Fault.
Bit 0 - Cycle Fault - When the Controller Unit is operating in the coordinated mode and cycling diagnostics indicate that a serviceable call exists that has not been serviced for two cycles.
Once set, a bit shall maintain it's state as long as the condition exists."
::= { unit 8 }

2.4.9 Short Alarm Status

shortAlarmStatus OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"Short Alarm Mask (0 = False, 1 = True) as follows:

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Bit 7 - Critical Alarm; When the Stop Time input is active.
Bit 6 - Non-Critical Alarm; When an physical alarm input is active.
Bit 5 - Detector Fault; When any detectorAlarm fault occurs.
Bit 4 - Coordination Alarm; When the CU is not running the called pattern without offset correction within three cycles of the command. An offset correction requiring less than three cycles due to cycle overrun caused by servicing a pedestrian call shall not cause a Coordination Alarm.
Bit 3 - Local Override; When any external input or CU programming has prevented the device from responding to a system pattern command.
Bit 2 - Local Cycle Zero; When running coordinated and the local coord cycle timer has passed through zero.
Bit 1 - T&F Flash; When either the Local Flash or MMU Flash input becomes active.
Bit 0 - Preempt - When any of the CU Preempt inputs become active.
Once set, a bit shall maintain it's state as long as the condition exists."
::= { unit 9 }

2.4.10 Unit Control

unitControl OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to allow a remote entity to activate unit functions in the device (0 = False / Disabled, 1 = True / Enabled) as follows:
Bit 7 = Dimming Enable - when set to 1, causes channel dimming to operate as configured.
REFERENCE NEMA TS 2 Clause 3.9.2
Bit 6 = Interconnect - when set to 1, shall cause the interconnect inputs to operate at a higher priority than the timebase control (TBC On Line).
REFERENCE NEMA TS 2 Clause 3.6.2.3 and 3.8.3
Bit 5 = Walk Rest Modifier - when set to 1, causes non-actuated phases to remain in the timed-out Walk state (rest in Walk) in the absence of a serviceable conflicting call.
REFERENCE NEMA TS 2 Clause 3.5.5.5.13
Bit 4 = Call to Non-Actuated 2 - when set to 1, causes any phase(s) appropriately programmed in the phaseOptions object to operate in the Non-Actuated Mode.
REFERENCE NEMA TS 2 Clause 3.5.5.5.8
Bit 3 = Call to Non-Actuated 1 - when set to 1, causes any phase(s) appropriately programmed in the phaseOptions object to operate in the Non-Actuated Mode.
REFERENCE NEMA TS 2 Clause 3.5.5.5.8
Bit 2 = External Minimum Recall - when set to 1, causes a recurring demand on all vehicle phases for a minimum vehicle service.
REFERENCE NEMA TS 2 Clause 3.5.5.5.9
Bit 1 = Reserved
Bit 0 = Reserved
When a bit = 1, the device shall activate the Unit control. When a bit = 0, the device shall not activate the Unit control.

The device shall reset this object to ZERO when in BACKUP Mode. A write to this object shall reset the BACKUP timer."
::= { unit 10 }

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2.4.11 Maximum Alarm Groups

```
maxAlarmGroups OBJECT-TYPE
        SYNTAX  INTEGER(0..255)
        ACCESS   read-only
        STATUS   optional
        DESCRIPTION
             "This object contains the maximum number of alarm groups (8 alarm inputs per group) this
             device supports. This object indicates the maximum rows which shall appear in the
             alarmGroupTable object."
::= { unit 11 }
```

2.4.12 Alarm Group Table

```
alarmGroupTable OBJECT-TYPE
        SYNTAX  SEQUENCE OF AlarmGroupEntry
        ACCESS   not-accessible
        STATUS   optional
        DESCRIPTION
             "This table contains alarm input status in groups of eight inputs. The number of rows in this
             table is equal to the maxAlarmGroups object."
::= { unit 12 }

alarmGroupEntry OBJECT-TYPE
        SYNTAX  AlarmGroupEntry
        ACCESS  not-accessible
        STATUS   mandatory
        DESCRIPTION
             "Status for eight alarm inputs."
        INDEX  { alarmGroupNumber }
::= { alarmGroupTable 1 }

AlarmGroupEntry::= SEQUENCE {
        alarmGroupNumber  INTEGER,
        alarmGroupState     INTEGER}
```

2.4.12.1 Alarm Group Number

```
alarmGroupNumber OBJECT-TYPE
     SYNTAX  INTEGER (0..255)
     ACCESS   read-only
     STATUS   mandatory
     DESCRIPTION
          "The alarm group number for objects in this row. This value shall not exceed the
          maxAlarmGroups object value."
::= { alarmGroupEntry 1 }
```

2.4.12.2 Alarm Group State

```
alarmGroupState OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
             "Alarm input state bit field. When a bit = 1, the associated physical alarm input is active.
             When a bit = 0, the associated alarm input is NOT active.
```

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Bit 7 = Alarm Input number = (alarmGroupNumber * 8)
Bit 6 = Alarm Input number = (alarmGroupNumber * 8) -1
Bit 5 = Alarm Input number = (alarmGroupNumber * 8) -2
Bit 4 = Alarm Input number = (alarmGroupNumber * 8) -3
Bit 3 = Alarm Input number = (alarmGroupNumber * 8) -4
Bit 2 = Alarm Input number = (alarmGroupNumber * 8) -5
Bit 1 = Alarm Input number = (alarmGroupNumber * 8) -6
Bit 0 = Alarm Input number = (alarmGroupNumber * 8) -7"
::= {alarmGroupEntry 2 }

2.4.13 Maximum Special Function Outputs

```
maxSpecialFunctionOutputs   OBJECT-TYPE
        SYNTAX   INTEGER (0..255)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
            "The Maximum Number of Special Functions this Actuated Controller Unit supports."
::= { unit 13 }
```

2.4.14 Special Function Output Table

```
specialFunctionOutputTable   OBJECT-TYPE
        SYNTAX   SEQUENCE OF SpecialFunctionOutputEntry
        ACCESS   not-accessible
        STATUS   optional
        DESCRIPTION
            "A table containing Actuated Controller Unit special function output objects. The number of
            rows in this table is equal to the maxSpecialFunctionOutputs object."
::= { unit 14 }

specialFunctionOutputEntry   OBJECT-TYPE
        SYNTAX   SpecialFunctionOutputEntry
        ACCESS   not-accessible
        STATUS   mandatory
        DESCRIPTION
            "Control for  Actuated Controller Unit system special functions."
        INDEX   { specialFunctionOutputNumber }
::= { specialFunctionOutputTable 1 }

SpecialFunctionOutputEntry ::= SEQUENCE {
        specialFunctionOutputNumber                INTEGER,
        specialFunctionOutputState                 INTEGER }
```

2.4.14.1 Special Function Output Number

```
specialFunctionOutputNumber OBJECT-TYPE
        SYNTAX   INTEGER (0..255)
        ACCESS   read-write
        STATUS   mandatory
        DESCRIPTION
            "The special function output number associated with the  specialFunctionOutputState object
            in this row. This value shall not exceed the maxSpecialFunctionOutputs object value."
::= { specialFunctionOutputEntry 1 }
```

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2.4.14.2 Special Function Output Control

```
specialFunctionOutputState OBJECT-TYPE
        SYNTAX  INTEGER (0..1)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The special function output (logical or physical)on the device may be controlled by this
            object.  When this object is non-zero then the associated special function output signal shall
            be ON.  When this object is zero then the associated special function output signal shall be
            OFF  A read of this object shall reflect the current state of the special function output."
::= { specialFunctionOutputEntry  2 }
```

2.5 COORDINATION PARAMETERS

```
coord OBJECT IDENTIFIER
::= { asc  4 }

-- The coord node contains objects that support coordination configuration, status and control functions for
-- the device.
```

2.5.1 Coord Operational Mode Parameter

```
coordOperationalMode  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object defines the operational mode for coordination.  The possible modes are:
                Value Description
                0     Automatic - this mode provides for coord operation, free, and flash to be
                      determined automatically by the possible sources (i.e. Interconnect, Time Base, or
                      System Commands).
                1-253 Manual Pattern - these modes provides for Coord operation running this pattern.
                      This selection of pattern overrides all other pattern commands.
                254   Manual Free - this mode provides for Free operation without coordination or
                      Automatic Flash from any source.
                255   Manual Flash - this mode provides for Automatic Flash without coordination or Free
                      from any source."
        REFERENCE
            "NEMA TS 2 Clause 3.6.2.4"
::= { coord 1 }
```

2.5.2 Coord Correction Mode Parameters

```
coordCorrectionMode  OBJECT-TYPE

        SYNTAX  INTEGER {  other (1),
                           dwell (2),
                           shortway (3),
                           addOnly (4) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object defines the Coord Correction Mode. The possible modes are:
                other; the coordinator establishes a new offset by a mechanism not defined in this
                       standard.
```

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dwell; when changing offset, the coordinator shall establish a new offset by dwelling in the coord phase(s) until the desired offset is reached.
shortway (Smooth); when changing offset, the coordinator shall establish a new offset by adding or subtracting to/from the timings in a manner that limits the cycle change. This operation is performed in a device specific manner.
addOnly; when changing offset, the coordinator shall establish a new offset by adding to the timings in a manner that limits the cycle change. This operation is performed in a device specific manner."

::= { coord 2 }

2.5.3 Coord Maximum Mode Parameters

```
coordMaximumMode  OBJECT-TYPE
        SYNTAX  INTEGER {  other (1),
                           maximum1 (2),
                           maximum2 (3),
                           maxInhibit (4) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
          "This object defines the Coord Maximum Mode. The possible modes are:
                other; the maximum mode is determined by some other mechanism not defined in this
                        standard.
                maximum1; the internal Maximum 1 Timing shall be effective while coordination is
                        running a pattern.
                maximum2; the internal Maximum 2 Timing shall be effective while coordination is
                        running a pattern.
                maxInhibit; the internal Maximum Timing shall be inhibited while coordination is running a
                        pattern."
::= { coord 3 }
```

2.5.4 Coord Force Mode Parameters

```
coordForceMode  OBJECT-TYPE
        SYNTAX  INTEGER {  other(1),
                           floating (2),
                           fixed (3) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object defines the Pattern Force Mode. The possible modes are:
                other; the CU implements a mechanism not defined in this standard.
                floating; each phase will be forced the split time after it becomes active. This allows
                        unused split time to revert to the coord phase.
                fixed; each phase will be forced at a fixed position in the cycle. This allows unused split
                        time to revert to the following phase."
::= { coord 4 }
```

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2.5.5 Maximum Patterns Parameters

```
maxPatterns  OBJECT-TYPE
        SYNTAX  INTEGER (0..253)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The maximum number of Patterns this Actuated Controller Unit supports. This object
            indicates how many rows are in the patternTable object. Pattern 254 is always Flash mode
            and pattern 255 is always Free mode."
::= { coord 5 }
```

2.5.6 Pattern Table Type

```
patternTableType  OBJECT-TYPE
        SYNTAX  INTEGER {   other (1),
                            patterns (2),
                            offset3 (3),
                            offset5 (4) }
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This object provides information about any special organizational structure required for the
            pattern table.  The defined structures are as follows:
                other -     The pattern table setup is not described in this standard, refer to device
                            manual.
                patterns -  Each row of the pattern table represents a unique pattern and has no
                            dependencies on other rows.
                offset3 -   The pattern table is organized into plans which have three offsets.  Each plan
                            uses three consecutive rows.  Only the offsetTime value may vary between
                            each of the three rows.  Plan 1 is contained in rows 1,  2 and 3,  Plan 2 is
                            contained in rows 4, 5 and 6, Plan 3 is in rows 7, 8 and 9, etc..
                offset5 -   The pattern table is organized into plans which have five offsets.  Each plan
                            occupies five consecutive rows.  Only the offsetTime value may vary between
                            each of the rows.  Plan 1 is contained in rows 1, 2, 3, 4 and 5, Plan 2 is
                            contained in rows , 6,7, 8, 9 and 10, Plan 3 is contained in rows  11, 12, 13, 14
                            and 15, etc..."
        REFERENCE
            "NEMA TS 2 Clause 3.6.2.1 and 3.6.2.2"
::= { coord 6 }
```

2.5.7 Pattern Table

```
patternTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF PatternEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit coordination Pattern parameters. The number of
            rows in this table is equal to the maxPatterns object."
::= { coord 7 }
```

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```
patternEntry  OBJECT-TYPE
        SYNTAX  PatternEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit pattern."
        INDEX  { patternNumber }
::= { patternTable 1 }

PatternEntry ::= SEQUENCE {
        patternNumber                   INTEGER,
        patternCycleTime                INTEGER,
        patternOffsetTime               INTEGER,
        patternSplitNumber              INTEGER,
        patternSequenceNumber           INTEGER }
```

2.5.7.1 Pattern Number Entry

```
patternNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..253)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The pattern number for objects in this row. This value shall not exceed the maxPatterns
            object value."
::= { patternEntry 1 }
```

2.5.7.2 Pattern Cycle Time

```
patternCycleTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The patternCycleTime object specifies the length of the pattern cycle in seconds (NEMA TS
            2 range: 30-255).  A pattern cycle time less than adequate to service the minimum
            requirements of all phases shall result in Free mode.  If the pattern cycle time is zero  and
            the associated split table (if any)  contains values greater than zero then the CU shall utilize
            the split time values as maximum values for each phase."
        REFERENCE
            "NEMA TS 2 Clause 3.6.2.1.1"
::= { patternEntry 2 }
```

2.5.7.3 Pattern Offset Time Parameter

```
patternOffsetTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The patternOffsetTime defines by how many seconds (NEMA TS 2 range: 0-254) the local
            time zero shall lag the system time zero (synchronization pulse) for this pattern.. An offset
            value equal to or greater than the cycle time shall result in Free being the operational mode.
            While this condition exists, the Local Free bit of unitAlarmStatus and the LocalOverride bit of
            shortAlarmStatus shall be set to one (1)."
        REFERENCE
            "NEMA TS 2 Clause 3.6.2.2"
::= { patternEntry 3 }
```

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2.5.7.4 Pattern Split Number Parameter

```
patternSplitNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object is used to locate information in the splitTable to use for this pattern. This value
            shall not exceed the maxSplits object value."
::= { patternEntry 4 }
```

2.5.7.5 Pattern Sequence Number Parameter

```
patternSequenceNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object is used to locate information in the sequenceTable to use with this pattern. This
            value shall not exceed the maxSequences object value."
::= { patternEntry 5 }
```

2.5.8 Maximum Splits

```
maxSplits  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The maximum number of Split Plans this Actuated Controller Unit supports. This object
            indicates how many Split plans are in the splitTable object."
::= { coord 8 }
```

2.5.9 Split Table

```
splitTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF SplitEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit coordination split parameters. The number of
            rows in this table is equal to maxSplits."
::= { coord 9 }

splitEntry  OBJECT-TYPE
        SYNTAX  SplitEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Split type Parameters for a specific Actuated Controller Unit phase."
        INDEX  { splitNumber, splitPhase }
::= { splitTable 1 }
```

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```
SplitEntry ::= SEQUENCE {
    splitNumber         INTEGER,
    splitPhase          INTEGER,
    splitTime           INTEGER,
    splitMode           INTEGER,
    splitCoordPhase     INTEGER }
```

2.5.9.1 Split Number

```
splitNumber  OBJECT-TYPE
        SYNTAX  INTEGER (1..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The object defines which rows of the split table comprise a split group. All rows that have the
            same splitNumber are in the same split group. The value of this object shall not exceed the
            maxSplits object value."
::= { splitEntry 1 }
```

2.5.9.2 Split Phase Number

```
splitPhase  OBJECT-TYPE
        SYNTAX  INTEGER (1..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The phase number for objects in this row. The value of this object shall not exceed the
            maxPhases object value."
::= { splitEntry 2 }
```

2.5.9.3 Split Time Parameter

```
splitTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The time in seconds the splitPhase is allowed to receive (i.e. before a Force Off is applied)
            when constant demands exist on all phases. In floating coordForceMode, this is always the
            maximum time a non-coordinated phase is allowed to receive. In fixed coordForceMode, the
            actual allowed time may be longer if a previous phase gapped out.
            The splitTime includes all phase clearance times for the associated phase. The split time
            shall be longer than the sum of the phase minimum service requirements (Minimum Green,
            Yellow Change, Red Clearance, Walk, Pedestrian Clearance, etc.) for the phase. When the
            time is NOT adequate to service the minimum service requirements of the phase, Free Mode
            shall be the result.
            If the cycleTime entry of the associated patternTable entry is zero (i.e. the device is in Free
            Mode), then the value of this object shall be applied as a maximum time for the associated
            phase.
            If the critical path through the phase diagram is less than the cycleTime entry of the
            associated patternTable entry, all extra time is allotted to the coordination phase in each ring.
            If the critical path through the phase diagram is greater than the cycleTime entry of the
            associated patternTable entry (and the cycleTime is not zero) the device shall operate in the
            Free Mode.
```

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While the Free Mode condition exists, the Local Override bit of shortAlarm shall be set to one (1)."

REFERENCE
"NEMA TS 2 Clause 3.6.2.1.2"

::= { splitEntry 3 }

2.5.9.4 Split Mode Parameter

```
splitMode  OBJECT-TYPE
        SYNTAX  INTEGER {  other(1),
                           none (2),
                           minimumVehicleRecall (3),
                           maximumVehicleRecall (4),
                           pedestrianRecall (5),
                           maximumVehicleAndPedestrianRecall (6),
                           phaseOmitted (7) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object defines operational characteristics of the phase. The following options are
            available:
                other; the operation is not specified in this standard
                none; no split mode control.
                minimumVehicleRecall; this phase operates with a minimum vehicle recall.
                maximumVehicleRecall; this phase operates with a maximum vehicle recall.
                pedestrianRecall; this phase operates with a pedestrian recall.
                maximumVehicleAndPedestrianRecall; this phase operates with a maximum vehicle &
                        pedestrian recall.
                phaseOmitted; this phase is omitted."
::= { splitEntry 4 }
```

2.5.9.5 Split Coordinated Phase

```
splitCoordPhase  OBJECT-TYPE
        SYNTAX  INTEGER (0..1)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "To select the associated phase as a coordinated phase this object shall be set to TRUE
            (non zero)."
::= { splitEntry 5 }
```

2.5.10 Coordination Pattern Status

```
coordPatternStatus  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This object defines the running coordination pattern / mode in the device.  The possible
            values are:
                Value   Description
                0       Not used
                1-253   Pattern, indicates the currently running pattern
                254     Free, indicates Free operation without coordination.
                255     Flash, indicates Automatic Flash without coordination."
::= { coord 10 }
```

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2.5.11 Local Free Status

```
localFreeStatus  OBJECT-TYPE
        SYNTAX  INTEGER {  other(1),
                           notFree(2),
                           commandFree(3),
                           transitionFree(4),
                           inputFree(5),
                           coordFree(6),
                           badPlan(7),
                           badCycleTime(8),
                           splitOverrun (9),
                           invalidOffset (10),
                           failed(11) }
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Free modes:
               notFree - The unit is not running in free mode.
               commandFree - the current pattern command is the Free mode pattern.
               transitionFree - the CU has a pattern command but is cycling to a point to begin
                     coordination.
               inputFree - one of the CU inputs cause it to not respond to coordination.
               coordFree - the CU programming for the called pattern is to run Free.
               badPlan - Free - the called pattern is invalid.
               badCycleTimeFree - the specified cycle time is not adequate to service the all phase
                     minimum service requirements.
               splitOverrun - Free - the sum of the critical path splitTime's exceed the programmed
                     patternCycleTime value..
               invalidOffset - Free - the programmed patternOffsetTime value exceeds the programmed
                     patternCycleTime value.
               failedFree - cycling diagnostics have called for Free.
               other - Some other condition has caused the device to run in free mode."
::= { coord 11 }
```

2.5.12 Coordination Cycle Status

```
coordCycleStatus  OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Local Cycle Timer position for the running pattern in the device. Value 0 to 510. Count
            down from current cycle's Cycle Length to ZERO.  This value may exceed the cycleTime
            value during correction cycle's (cycleTime + dwell )."
::= { coord 12 }
```

2.5.13 Coordination Sync Status

```
coordSyncStatus  OBJECT-TYPE
        SYNTAX  INTEGER (0..65536)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Sync Cycle Timer position for the running pattern in the device. Value 0 to 510.  It
            represents the time that has elapsed since system time zero."
::= { coord 13 }
```

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2.5.14 System Pattern Control

systemPatternControl OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to establish the Called System Pattern / Mode for the device. The possible values are:

Value	Description
0	Standby - the system relinquishes control of the device.
1-253	Pattern - these values indicate the system commanded pattern
254	Free - this value indicates a call for Free
255	Flash - this value indicates a call for Automatic Flash

If an unsupported / invalid pattern is called, Free shall be the operational mode.
The value of this object is ignored in BACKUP mode.
A write to this object shall reset the BACKUP timer to ZERO."
::= { coord 14 }

2.5.15 System Sync Control

systemSyncControl OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"This object is used to set the current System Sync Cycle Timer in the Unit to a Value 0 to 255. The device shall recognize a write to this object as a command to set the timer equal to the value in the object. The Sync Cycle Timer counts up from 0. When the value in the object is 255, the System Sync Cycle Timer shall be referenced to the local Time Base in accordance with its programming.
This CU must maintain an accuracy of 0.1 seconds based on the receipt of the SET packet.
The value of this object is ignored when in BACKUP Mode.
A write to this object shall reset the BACKUP timer to ZERO."
::= { coord 15 }

2.6 TIME BASE PARAMETERS

timebase OBJECT IDENTIFIER
::= { asc 5 }

-- "This object is an identifier used to group all objects for support of timebase functions. If a device
-- implements timebase functions then these objects shall be supported."

2.6.1 Time Base Pattern Sync Parameter

timebasePatternSync OBJECT-TYPE
SYNTAX INTEGER (0..65535)
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Pattern Sync Reference in minutes past midnight. When the value is 0xFFFF, the controller unit shall use the Action time as the Sync Reference for that pattern."
REFERENCE
"NEMA TS 2 Clause 3.8.2"
::= { timebase 1 }

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2.6.2 Maximum Time Base Actions

```
maxTimebaseAscActions  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Actions this device supports. This object indicates the maximum
            rows which shall appear in the timebaseAscActionTable object."
::= { timebase 2 }
```

2.6.3 Time Base ASC Action Table

```
timebaseAscActionTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF TimebaseAscActionEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit Time Base action parameters. The number of
            rows in this table is equal to the maxTimebaseAscActions object."
::= { timebase 3 }

timebaseAscActionEntry  OBJECT-TYPE
        SYNTAX  TimebaseAscActionEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Action Parameters for a Actuated Controller Unit Time Base Program."
        INDEX  { timebaseAscActionNumber }
::= { timebaseAscActionTable 1 }

TimebaseAscActionEntry ::= SEQUENCE {
        timebaseAscActionNumber          INTEGER,
        timebaseActionPattern            INTEGER,
        timebaseActionAuxillaryFunction  INTEGER,
        timebaseActionSpecialFunction    INTEGER }
```

2.6.3.1 Time Base Action Number Entry

```
timebaseAscActionNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The time base Action number for objects in this row. This value shall not exceed the
            maxTimebaseAscActions object value."
::= { timebaseAscActionEntry 1 }
```

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2.6.3.2 Time Base Action Pattern Parameter

```
timebaseActionPattern  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The Pattern that shall be active when this Action is active. The value shall not exceed the
            value of maxPatterns. A pattern of zero indicates that no pattern is being selected."
::= { timebaseAscActionEntry 2 }
```

2.6.3.3 Time Base Action Auxiliary Function Parameter

```
timebaseActionAuxillaryFunction  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The Auxiliary functions that shall be active when this Action is active.
                Bit  Function
                0    Auxiliary function 1 enabled if set (non-zero), disabled if clear (zero).
                1    Auxiliary function 2 enabled if set (non-zero), disabled if clear (zero).
                2    Auxiliary function 3 enabled if set (non-zero), disabled if clear (zero).
                3-7  Reserved"
::= { timebaseAscActionEntry 3 }
```

2.6.3.4 Time Base Action Special Function Parameter

```
timebaseActionSpecialFunction  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The Special Functions that shall be active when this Action is active.
                Bit 7 - Special Function 8 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 6 - Special Function 7 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 5 - Special Function 6 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 4 - Special Function 5 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 3 - Special Function 4 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 2 - Special Function 3 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 1 - Special Function 2 (0 =False / Disabled, 1 = True /  Enabled)
                Bit 0 - Special Function 1 (0 =False / Disabled, 1 = True /  Enabled)"
::= { timebaseAscActionEntry 4 }
```

2.6.4 Time Base ASC Action Status

```
timebaseAscActionStatus  OBJECT-TYPE
        SYNTAX  INTEGER(0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This object indicates the current time base Action Table row that will be used when the CU
            is in Time Base operation.  A value of zero indicates that no time base Action is selected."
::= { timebase 4 }
```

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2.7 PREEMPT PARAMETERS

```
preempt OBJECT IDENTIFIER
    ::= { asc 6 }
-- The preempt node contains objects that support preempt input functions for the device.
```

2.7.1 Maximum Preempts

```
maxPreempts  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Preempts this Actuated Controller Unit supports. This object
            indicates the maximum rows which shall appear in the preemptTable object."
        REFERENCE
            "NEMA TS 2 Clause 3.7"
::= { preempt 1 }
```

2.7.2 Preempt Table

```
preemptTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF PreemptEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit preemption parameters. The number of rows in
            this table is equal to the maxPreempts object."
::={ preempt 2 }

preemptEntry  OBJECT-TYPE
        SYNTAX  PreemptEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit preemptor."
        INDEX   { preemptNumber }

::={ preemptTable 1}

PreemptEntry ::= SEQUENCE {
        preemptNumber           INTEGER,
        preemptControl          INTEGER,
        preemptLink             INTEGER,
        preemptDelay            INTEGER,
        preemptMinimumDuration  INTEGER,
        preemptMinimumGreen     INTEGER,
        preemptMinimumWalk      INTEGER,
        preemptEnterPedClear    INTEGER,
        preemptTrackGreen       INTEGER,
        preemptDwellGreen       INTEGER,
        preemptMaximumPresence  INTEGER,
        preemptTrackPhase       OCTET STRING,
        preemptDwellPhase       OCTET STRING,
        preemptDwellPed         OCTET STRING,
        preemptExitPhase        OCTET STRING ,
        preemptState            INTEGER }
```

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2.7.2.1 Preempt Number

```
preemptNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The preempt number for objects in this row. The value shall not exceed the maxPreempts
            object value."
::= { preemptEntry 1 }
```

2.7.2.2 Preempt Control Parameter

```
preemptControl  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Preempt Miscellaneous Control Parameter Mask ( 0 = False / Disabled, 1 = True /  Enabled)
            as follows:
                Bit  Function
                7-4
                3    Flash Dwell - the CU shall cause the phases listed in the preemptDwellPhase object
                     to flash Yellow during the Dwell phase.  All active phases not listed in the
                     preemptDwellPhase shall flash Red.  If any conflicting phase numbers are listed in
                     the preemptDwellPhase then all active phases shall flash Red.
                     This control is optional.
                2    Preempt Override preemptNumber + 1 - provide a means to define whether this
                     preempt shall NOT override the next higher numbered Preempt.  When set (1) this
                     preempt shall not override the next higher numbered preempt.  This parameter shall
                     be ignored when preemptNumber equals maxPreempts.
                1    Preempt Override Flash - provide a means to define whether this preempt shall NOT
                     override Automatic Flash.  When set (1) this preempt shall not override Automatic
                     Flash.
                0    Non-Locking Memory - provide a means to enable an operation which does not
                     require detector memory. When set (1) a preempt sequence shall not occur if the
                     preempt input terminates prior to expiration of the preemptDelay time."
        REFERENCE
            "NEMA TS 2 Clause 3.7.2.1 and 3.7.2.2"
::= { preemptEntry 2 }
```

2.7.2.3 Preempt Link Parameter

```
preemptLink  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object provides a means to define a higher priority preempt to be combined (linked)
            with this preempt. At the end of Dwell time, the linked preempt shall receive an automatic call
            which shall be maintained as long as the demand for this preempt is active. Any value that is
            not a higher priority preempt or a valid preempt shall be ignored. The value shall not exceed
            the maxPreempts object value."
::= { preemptEntry 3 }
```

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2.7.2.4 Preempt Delay Parameter

```
preemptDelay  OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Preempt Delay Time in seconds ( 0-600 sec). This value determines the time the preempt
            input shall be active prior to initiating any preempt sequence.  A non-locking preempt input
            which is removed prior to the completion of this time shall not cause a preempt sequence to
            occur."
::= { preemptEntry 4 }
```

2.7.2.5 Preempt Duration Parameter

```
preemptMinimumDuration  OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Preempt Minimum Duration Time in seconds (0..65535). This value determines the
            minimum time during which the preempt is active.  Duration begins timing at the end of
            Preempt Delay (if non zero) and will prevent an exit from the Dwell state until this time has
            elapsed."
::= { preemptEntry 5 }
```

2.7.2.6 Preempt Minimum Green Parameter

```
preemptMinimumGreen  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Preempt Minimum Green Time in seconds (0-255 sec). A preempt initiated transition shall
            not cause the termination of an existing Green prior to its display for lesser of the phase's
            Minimum Green time or this period."
::= { preemptEntry 6 }
```

2.7.2.7 Preempt Minimum Walk Parameter

```
preemptMinimumWalk  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Preempt Minimum Walk Time in seconds (0-255 sec). A preempt initiated transition shall not
            cause the termination of an existing Walk prior to its display for the lesser of the phase's
            Minimum Walk time or this period."
::= { preemptEntry 7 }
```

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2.7.2.8 Preempt Enter Pedestrian Clear Parameter

```
preemptEnterPedClear  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Enter Ped ClearTime in seconds (0-255 sec). This parameter controls the ped clear timing
            for a normal Walk signal terminated by a preempt initiated transition.  A preempt initiated
            transition shall not cause the termination of a Pedestrian Clearance prior to its display for the
            lesser of the phase's Pedestrian Clearance time or this period."
::= { preemptEntry 8 }
```

2.7.2.9 Preempt Track Green Parameter

```
preemptTrackGreen  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Track Clear Green Time in seconds (0-255 sec). This parameter controls the green timing
            for the track clearance movement. The phase(s) active during the Track Green interval are
            enabled in preemptTrackPhase object."
::= { preemptEntry 9 }
```

2.7.2.10 Preempt Minimum Dwell Parameter

```
preemptDwellGreen  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Minimum Dwell Time in seconds (1-255 sec). This parameter controls the minimum timing
            for the dwell movement. The phase(s) active during the Dwell interval are enabled in
            preemptDwellPhase object.

            The Dwell interval shall not terminate prior to the completion of Preempt Duration Time,
            Preempt Dwell Time, & the call is no longer present."
::= { preemptEntry 10 }
```

2.7.2.11 Preempt Maximum Presence Parameter

```
preemptMaximumPresence OBJECT-TYPE
        SYNTAX  INTEGER (0..65535)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Preempt Maximum Presence time in seconds (0-65535 sec).  This value determines the
            maximum time which a preempt call may remain active and be considered valid.  When the
            preempt call has been active for this time period, the CU shall return to normal operation.
            This preempt call shall be considered invalid until such time as a change in state occurs (no
            longer active).  When set to zero the preempt maximum presence time is disabled."
::= { preemptEntry 11 }
```

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2.7.2.12 Preempt Track Phase Parameter

```
preemptTrackPhase  OBJECT-TYPE
        SYNTAX  OCTET STRING
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Each octet within the octet string contains a phaseNumber(binary value) that shall be active
            during the Preempt Track Green interval."
::= { preemptEntry 12 }
```

2.7.2.13 Preempt Dwell Phase Parameters

```
preemptDwellPhase  OBJECT-TYPE
        SYNTAX  OCTET STRING
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Each octet within the octet string contains a phaseNumber (binary value)that is allowed
            during the Preempt Dwell interval."
::= { preemptEntry 13 }
```

2.7.2.14 Preempt Dwell Ped Parameters

```
preemptDwellPed  OBJECT-TYPE
        SYNTAX  OCTET STRING
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "Each octet within the octet string contains a phaseNumber (binary value)indicating a
            pedestrian movement that is allowed during the Preempt Dwell interval."
::= { preemptEntry 14 }
```

2.7.2.15 Preempt Exit Phase Parameters

```
preemptExitPhase  OBJECT-TYPE
        SYNTAX  OCTET STRING
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Each octet within the octet string contains a phaseNumber (binary value)that shall be active
            following Preempt."
::= { preemptEntry 15 }
```

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2.7.2.16 Preempt State

```
preemptState OBJECT-TYPE
        SYNTAX  INTEGER {   other (1),
                            notActive (2),
                            notActiveWithCall (3),
                            entryStarted (4),
                            trackService (5),
                            dwell (6),
                            linkActive (7),
                            exitStarted (8),
                            maxPresence (9) }
        ACCESS  read-only
        STATUS  optional
        DESCRIPTION
            "Preempt State provides status on which state the associated preempt is in.  The states are
            as follows:
                State               Description
                notActive           preempt input is not active, this preempt is not active.
                notActiveWithCall   preempt input is active, preempt service has not started.
                entryStarted        preempt service is timing the entry intervals.
                trackService        preempt service is timing the track intervals.
                dwell               preempt service is timing the dwell intervals.
                linkActive          preempt service is performing linked operation.
                exitStarted         preempt service is timing the exit intervals.
                maxPresence         preempt input has exceeded maxPresence time
                other               preempt service is not specified in this standard."
::= { preemptEntry 16}
```

2.7.3 Preempt Control Table

```
preemptControlTable OBJECT-TYPE
        SYNTAX SEQUENCE OF PreemptControlEntry
        ACCESS not-accessible
        STATUS optional
        DESCRIPTION
            "This table contains the control objects that allow the preempts to be activated remotely.
            There shall be one control object for each preempt input supported by the device.  The
            number of rows in this table shall be equal to maxPreempts."
::= { preempt 3 }

preemptControlEntry  OBJECT-TYPE
        SYNTAX  PreemptControlEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Control objects for each preempt input. These objects allow the system to activate preempt
            functions remotely."
        INDEX  { preemptControlNumber }
::= { preemptControlTable 1 }

PreemptControlEntry ::= SEQUENCE {
        preemptControlNumber                INTEGER,
        preemptControlState                 INTEGER}
```

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2.7.3.1 Preempt Control Number

```
preemptControlNumber  OBJECT-TYPE
        SYNTAX   INTEGER (0..255)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
            "This object shall indicate the preempt input number controlled by the associated
            preemptControlState object in this row."
::= { preemptControlEntry  1 }
```

2.7.3.2 Preempt Control State

```
preemptControlState OBJECT-TYPE
        SYNTAX   INTEGER (0..1)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
            "This object when set to ON (non-zero) shall cause the associated preempt actions to occur
            unless the actions have already been started by the physical preempt input. The preempt
            shall remain active as long as this object is ON or the physical preempt input is ON. This
            object when set to OFF (zero) shall cause the physical preempt input to control the
            associated preempt actions.
            The value of this object is ignored in BACKUP mode. A write to this object shall reset the
            BACKUP timer."
::= { preemptControlEntry  2 }
```

2.8 RING PARAMETERS

```
ring  OBJECT IDENTIFIER
    ::= { asc  7 }
--The ring node contains objects that support ring configuration, status and control functions in the device.
```

2.8.1 Maximum Rings

```
maxRings   OBJECT-TYPE
        SYNTAX   INTEGER (0..255)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
            "The value of this object shall specify the maximum number of rings this device supports."
::= { ring 1 }
```

2.8.2 Maximum Sequences

```
maxSequences  OBJECT-TYPE
        SYNTAX   INTEGER (0..255)
        ACCESS   read-only
        STATUS   mandatory
        DESCRIPTION
            "The value of this object shall specify the maximum number of sequence plans this device
            supports."
::= { ring 2 }
```

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2.8.3 Sequence Table

```
sequenceTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF SequenceEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "This table contains all the sequence plans for the controller.  A sequence plan shall consist
            of one row for each ring that the CU supports.  Each row defines the phase service order for
            that ring."
::= { ring 3 }

sequenceEntry  OBJECT-TYPE
        SYNTAX  SequenceEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Phase Sequence Parameters for an Actuated Controller Unit."
        INDEX  { sequenceNumber, sequenceRingNumber }
::= { sequenceTable 1 }

SequenceEntry ::= SEQUENCE {
        sequenceNumber                  INTEGER,
        sequenceRingNumber              INTEGER,
        sequenceData                    OCTET STRING }
```

2.8.3.1 Sequence Number

```
sequenceNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This number identifies a sequence plan.  Each row of the table contains the phase
            sequence for a ring.  A sequence plan shall consist of one row for each ring that defines the
            phase sequences for that ring."
::= { sequenceEntry 1 }
```

2.8.3.2 Sequence Ring Number

```
sequenceRingNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This number identifies the ring number this phase sequence applies to."
::= { sequenceEntry 2 }
```

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2.8.3.3 SequenceData

```
sequenceData  OBJECT-TYPE
        SYNTAX  OCTET STRING
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Each octet is a Phase Number (binary value) within the associated ring number. The phase
            number value shall not exceed the maxPhases object value. The order of phase numbers
            determines the phase sequence for the ring. The phase numbers shall not be ordered in a
            manner that would violate the devices compatibility group."
::= { sequenceEntry 3 }
```

2.8.4 Maximum Ring Control Groups

```
maxRingControlGroups OBJECT-TYPE
        SYNTAX          INTEGER (0..255)
        ACCESS          read-only
        STATUS          mandatory
        DESCRIPTION
            "The maximum number of Ring Control Groups (8 rings per group) this Actuated Controller
            Unit supports. This value is equal to TRUNCATE[(maxRings + 7) / 8]. This object indicates
            the maximum rows which shall appear in the ringControlGroupTable object."
::= { ring 4 }
```

2.8.5 Ring Control Group Table

```
ringControlGroupTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF RingControlGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit Ring Control in groups of eight rings. The
            number of rows in this table is equal to the maxRingControlGroups object."
::= { ring 5 }

ringControlGroupEntry  OBJECT-TYPE
        SYNTAX  RingControlGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Ring Control for eight Actuated Controller Unit rings."
        INDEX  { ringControlGroupNumber }
::= { ringControlGroupTable 1 }

RingControlGroupEntry ::= SEQUENCE {
        ringControlGroupNumber                  INTEGER,
        ringControlGroupStopTime                INTEGER,
        ringControlGroupForceOff                INTEGER,
        ringControlGroupMax2                    INTEGER,
        ringControlGroupMaxInhibit              INTEGER,
        ringControlGroupPedRecycle              INTEGER,
        ringControlGroupRedRest                 INTEGER,
        ringControlGroupOmitRedClear            INTEGER }
```

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2.8.5.1 Ring Control Group Number

```
ringControlGroupNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Ring Control Group number for objects in this row. This value shall not exceed the
            maxRingControlGroups object value."
::= { ringControlGroupEntry 1 }
```

2.8.5.2 Ring Stop Time Control

```
ringControlGroupStopTime  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object is used to allow a remote entity to stop timing in the device. When a bit = 1, the
            device shall activate the System Stop Time control for that ring.
                Bit 7 = Ring number = (ringControlGroupNumber * 8)
                Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
                Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
                Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
                Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
                Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
                Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
                Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7

            The value of this object is ignored in BACKUP Mode. A write to this object shall reset the
            Backup timer."
        REFERENCE
            "NEMA TS 2 Clause 3.5.4.1.6"
::= { ringControlGroupEntry 2 }
```

2.8.5.3 Ring Force Off Control

```
ringControlGroupForceOff  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object is used to allow a remote entity to terminate phases via a force off command in
            the device. When a bit = 1, the device shall activate the System Force Off control for that
            ring.
                Bit 7 = Ring number = (ringControlGroupNumber * 8)
                Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
                Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
                Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
                Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
                Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
                Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
                Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7
```

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The value of this object is ignored in BACKUP Mode. A write to this object shall reset the Backup timer."

REFERENCE
"NEMA TS 2 Clause 3.5.4.1.1"

::= { ringControlGroupEntry 3 }

2.8.5.4 Ring Max 2 Control

ringControlGroupMax2 OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS optional
DESCRIPTION
"This object is used to allow a remote entity to request maximum 2 timings in the device. When a bit = 1, the device shall activate the System Maximum 2 control for that ring.
Bit 7 = Ring number = (ringControlGroupNumber * 8)
Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7
The value of this object is ignored in BACKUP Mode. A write to this object shall reset the Backup timer."
REFERENCE
"NEMA TS 2 Clause 3.5.4.1.7"
::= { ringControlGroupEntry 4 }

2.8.5.5 Ring Max Inhibit Control

ringControlGroupMaxInhibit OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS optional
DESCRIPTION
"This object is used to allow a remote entity to request internal maximum timings be inhibited in the device. When a bit = 1, the device shall activate the System Max Inhibit control for that ring.
Bit 7 = Ring number = (ringControlGroupNumber * 8)
Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7

The value of this object is ignored in BACKUP Mode. A write to this object shall reset the Backup timer."
REFERENCE
"NEMA TS 2 Clause 3.5.4.1.3"
::= { ringControlGroupEntry 5 }

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2.8.5.6 Ring Ped Recycle Control

```
ringControlGroupPedRecycle  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "This object is used to allow a remote entity to request a pedestrian recycle in the device.
            When a bit = 1, the device shall activate the System Ped Recycle control for that ring.
                Bit 7 = Ring number = (ringControlGroupNumber * 8)
                Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
                Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
                Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
                Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
                Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
                Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
                Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7

            The value of this object is ignored in BACKUP Mode. A write to this object shall reset the
            Backup timer."
        REFERENCE
            "NEMA TS 2 Clause 3.5.4.1.5"
::= { ringControlGroupEntry 6 }
```

2.8.5.7 Ring Red Rest Control

```
ringControlGroupRedRest  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "This object is used to allow a remote entity to request red rest in the device. When a bit = 1,
            the device shall activate the System Red Rest control for that ring.
                Bit 7 = Ring number = (ringControlGroupNumber * 8)
                Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
                Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
                Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
                Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
                Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
                Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
                Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7

            The value of this object is ignored when in BACKUP Mode. A write to this object shall reset
            the Backup timer."
        REFERENCE
            "NEMA TS 2 Clause 3.5.4.1.2"
::= { ringControlGroupEntry 7 }
```

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2.8.5.8 Ring Omit Red Control

```
ringControlGroupOmitRedClear  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  optional
        DESCRIPTION
            "This object is used to allow a remote entity to omit red clearances in the device. When a bit
            = 1, the device shall activate the System Omit Red Clear control for that ring.
                Bit 7 = Ring number = (ringControlGroupNumber * 8)
                Bit 6 = Ring number = (ringControlGroupNumber * 8) - 1
                Bit 5 = Ring number = (ringControlGroupNumber * 8) - 2
                Bit 4 = Ring number = (ringControlGroupNumber * 8) - 3
                Bit 3 = Ring number = (ringControlGroupNumber * 8) - 4
                Bit 2 = Ring number = (ringControlGroupNumber * 8) - 5
                Bit 1 = Ring number = (ringControlGroupNumber * 8) - 6
                Bit 0 = Ring number = (ringControlGroupNumber * 8) - 7

            The value of this object is ignored in BACKUP Mode. A write to this object shall reset the
            Backup timer."
        REFERENCE
            "NEMA TS 2 Clause 3.5.4.1.4"
::= { ringControlGroupEntry 8 }
```

2.9 CHANNEL PARAMETERS

```
channel OBJECT IDENTIFIER
::= { asc 8 }
```

--This defines a node for supporting channel objects.

2.9.1 Maximum Channels

```
maxChannels  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Channels this Actuated Controller Unit supports. This object
            indicates the maximum rows which shall appear in the channelTable object."
::= { channel 1 }
```

2.9.2 Channel Table

```
channelTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF ChannelEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit channel parameters. The number of rows in this
            table is equal to the maxChannels object."
::= { channel 2 }
```

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```
channelEntry  OBJECT-TYPE
        SYNTAX  ChannelEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit channel."
        INDEX  { channelNumber }
::= { channelTable 1 }

ChannelEntry ::= SEQUENCE {
        channelNumber         INTEGER,
        channelControlSource  INTEGER,
        channelControlType    INTEGER,
        channelFlash          INTEGER,
        channelDim            INTEGER }
```

2.9.2.1 Channel Number

```
channelNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The channel number for objects in this row. This value shall not exceed the maxChannels
            object value."
::= { channelEntry 1 }
```

2.9.2.2 Channel Control Source Parameters

```
channelControlSource  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This object defines the channel control source (which Phase or Overlap). The value shall not
            exceed maxPhases or maxOverlaps as determined by channelControlType object:
                Value 00 = No Control (Not In Use)
                Value 01 = Phase 01 or Overlap A
                Value 02 = Phase 02 or Overlap B
                           ||
                Value 15 = Phase 15 or Overlap O
                Value 16 = Phase 16 or Overlap P
                           etc."
::= { channelEntry 2 }
```

2.9.2.3 Channel Control Type Parameters

```
channelControlType  OBJECT-TYPE
        SYNTAX  INTEGER {  other (1),
                           phaseVehicle (2),
                           phasePedestrian (3),
                           overlap (4) }
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "This object defines the channel control type (Vehicle Phase, Pedestrian Phase, or Overlap):
               phaseVehicle - The channel controls a vehicle phase display.
```

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phase Pedestrian - The channel controls a pedestrian phase display.
overlap - The channel controls an overlap display.
other - The channel controls an other type of display."
::= { channelEntry 3 }

2.9.2.4 Channel Flash Parameters

channelFlash OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"This object defines the channel state during Automatic Flash.
Bit Function
7-4 Reserved
3 Flash Alternate Half Hertz (Bit 0 = Off / Disabled & 1 = On / Enabled)
2 Flash Red (Bit 0 = Off / Red Dark & 1 = On / Flash Red)
1 Flash Yellow (Bit 0 = Off / Yellow Dark & 1 = On / Flash Yellow)
0 Reserved"
::= { channelEntry 4 }

2.9.2.5 Channel Dim Parameters

channelDim OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"This object defines the channel state during Dimming. Dimming shall be accomplished by the elimination of alternate one-half segments from the AC sinusoid applied to the field terminals.
Bit Function
7-4 Reserved
3 Dim Alternate Half Line Cycle (Bit 0 = Off / + half cycle & 1 = On / - half cycle)
2 Dim Red - Bit 0 = Off / Red Not Dimmed & 1 = On / Dimmed Red
1 Dim Yellow - Bit 0 = Off / Yellow Not Dimmed & 1 = On / Dimmed Yellow
0 Dim Green - Bit 0 = Off / Green Not Dimmed & 1 = On / Dimmed Green"
::= { channelEntry 5 }

2.9.3 Maximum Channel Status Groups

maxChannelStatusGroups OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-only
STATUS mandatory
DESCRIPTION
"The maximum number of Channel Status Groups (8 channels per group) this Actuated Controller Unit supports. This value is equal to TRUNCATE [(maxChannels + 7) / 8]. This object indicates the maximum rows which shall appear in the channelStatusGroupTable object."
::= { channel 3 }

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2.9.4 Channel Status Group Table

```
channelStatusGroupTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF ChannelStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit channel output (Red, Yellow, & Green) status in
            groups of eight channels. The number of rows in this table is equal to the
            maxChannelStatusGroups object."
::= { channel 4 }

channelStatusGroupEntry  OBJECT-TYPE
        SYNTAX  ChannelStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Red, Yellow, & Green Output Status for eight Actuated Controller Unit channels."
        INDEX  { channelStatusGroupNumber }
::= { channelStatusGroupTable 1 }

ChannelStatusGroupEntry ::= SEQUENCE {
        channelStatusGroupNumber                INTEGER,
        channelStatusGroupReds                  INTEGER,
        channelStatusGroupYellows               INTEGER,
        channelStatusGroupGreens                INTEGER }
```

2.9.4.1 Channel Status Group Number

```
channelStatusGroupNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The channelStatusGroup number for objects in this row. This value shall not exceed the
            maxChannelStatusGroups object value."
::= { channelStatusGroupEntry 1 }
```

2.9.4.2 Channel Status Group Reds

```
channelStatusGroupReds  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Channel Red Output Status Mask, when a bit = 1, the Channel Red is currently active.
            When a bit = 0, the Channel Red is NOT currently active.
                Bit 7 = Channel number = (channelStatusGroupNumber * 8)
                Bit 6 = Channel number = (channelStatusGroupNumber * 8) - 1
                Bit 5 = Channel number = (channelStatusGroupNumber * 8) - 2
                Bit 4 = Channel number = (channelStatusGroupNumber * 8) - 3
                Bit 3 = Channel number = (channelStatusGroupNumber * 8) - 4
                Bit 2 = Channel number = (channelStatusGroupNumber * 8) - 5
                Bit 1 = Channel number = (channelStatusGroupNumber * 8) - 6
                Bit 0 = Channel number = (channelStatusGroupNumber * 8) - 7"
::= { channelStatusGroupEntry 2 }
```

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2.9.4.3 Channel Status Group Yellows

```
channelStatusGroupYellows  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Channel Yellow Output Status Mask, when a bit = 1, the Channel Yellow is currently active.
            When a bit = 0, the Channel Yellow is NOT currently active.
                Bit 7 = Channel number = (channelStatusGroupNumber * 8)
                Bit 6 = Channel number = (channelStatusGroupNumber * 8) - 1
                Bit 5 = Channel number = (channelStatusGroupNumber * 8) - 2
                Bit 4 = Channel number = (channelStatusGroupNumber * 8) - 3
                Bit 3 = Channel number = (channelStatusGroupNumber * 8) - 4
                Bit 2 = Channel number = (channelStatusGroupNumber * 8) - 5
                Bit 1 = Channel number = (channelStatusGroupNumber * 8) - 6
                Bit 0 = Channel number = (channelStatusGroupNumber * 8) - 7"
::= { channelStatusGroupEntry 3 }
```

2.9.4.4 Channel Status Group Greens

```
channelStatusGroupGreens  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Channel Green Output Status Mask, when a bit = 1, the Channel Green is currently active.
            When a bit = 0, the Channel Green is NOT currently active.
                Bit 7 = Channel number = (channelStatusGroupNumber * 8)
                Bit 6 = Channel number = (channelStatusGroupNumber * 8) - 1
                Bit 5 = Channel number = (channelStatusGroupNumber * 8) - 2
                Bit 4 = Channel number = (channelStatusGroupNumber * 8) - 3
                Bit 3 = Channel number = (channelStatusGroupNumber * 8) - 4
                Bit 2 = Channel number = (channelStatusGroupNumber * 8) - 5
                Bit 1 = Channel number = (channelStatusGroupNumber * 8) - 6
                Bit 0 = Channel number = (channelStatusGroupNumber * 8) - 7"
::= { channelStatusGroupEntry 4 }
```

2.10 OVERLAP PARAMETERS

```
overlap  OBJECT IDENTIFIER
    ::= { asc 9 }
--"This node contains objects that configure, monitor and control overlap functions."
```

2.10.1 Maximum Overlaps

```
maxOverlaps  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Overlaps this Actuated Controller Unit supports. This object
            indicates the maximum number of rows which shall appear in the overlapTable object."
::= { overlap 1 }
```

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2.10.2 Overlap Table

```
overlapTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF OverlapEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit overlap parameters. The number of rows in this
            table is equal to the maxOverlaps object."
::= { overlap 2 }

overlapEntry  OBJECT-TYPE
        SYNTAX  OverlapEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Parameters for a specific Actuated Controller Unit overlap."
        INDEX  { overlapNumber }
::= { overlapTable 1 }

OverlapEntry ::= SEQUENCE {
        overlapNumber          INTEGER,
        overlapType            INTEGER,
        overlapIncludedPhases  OCTET STRING,
        overlapModifierPhases  OCTET STRING,
        overlapTrailGreen      INTEGER,
        overlapTrailYellow     INTEGER,
        overlapTrailRed        INTEGER }
```

2.10.2.1 Overlap Number

```
overlapNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The overlap number for objects in this row. The value shall not exceed the maxOverlaps
            object. The value maps to the Overlap as follows: 1 = Overlap A, 2 = Overlap B etc."
::= { overlapEntry 1 }
```

2.10.2.2 Overlap Type

```
overlapType  OBJECT-TYPE
        SYNTAX  INTEGER {   other(1),
                            normal (2),
                            minusGreenYellow (3) }
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "The type of overlap operation for this row.  The types are as follows:
               normal - The overlap output shall be controlled by the overlapIncludedPhases when this
                        type is selected.  The overlap output shall be green in the following situations:
                        (1) when an overlap included phase is green.
                        (2) when an overlap included phase is yellow (or red clearance) and an overlap
                        included phase is next.

                        The overlap output shall be yellow when an included phase is yellow and an
```

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overlap included phase is not next.
The overlap output shall be red whenever the overlap green and yellow are not ON.

minusGreenYellow - The overlap output shall be controlled by the overlapIncludedPhases and the overlapModifierPhases if this type is selected. The overlap output shall be green in the following situations:
(1) when an overlap included phase is green and an overlap modifier phase is NOT green.
(2) when an overlap included phase is yellow (or red clearance) and an overlap included phase is next and an overlap modifier phase is NOT green.

The overlap output shall be yellow when an overlap included phase is yellow and an overlap modifier phase is NOT yellow and an overlap included phase is not next.
The overlap output shall be red whenever the overlap green and yellow are not ON.

other - The overlap operates in another mode than those described above."
::= { overlapEntry 2 }

2.10.2.3 Overlap Included Phase Parameters

overlapIncludedPhases OBJECT-TYPE
SYNTAX OCTET STRING
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Each octet is a Phase (number) that shall be an included phase for the overlap. The phase number value shall not exceed the maxPhases object value. When an included phase output is green or when the CU is cycling between included phases, the overlap output shall be green."
::= { overlapEntry 3 }

2.10.2.4 Overlap Modifier Phase Parameters

overlapModifierPhases OBJECT-TYPE
SYNTAX OCTET STRING
ACCESS read-write
STATUS mandatory
DESCRIPTION
"Each octet is a Phase (number) that shall be a modifier phase for the overlap. The phase number value shall not exceed the maxPhases object value. The function of the modifier phase(s) is defined by the overlapType selected."
::= { overlapEntry 4 }

2.10.2.5 Overlap Trailing Green Parameter

overlapTrailGreen OBJECT-TYPE
SYNTAX INTEGER (0..255)
ACCESS read-write
STATUS mandatory
DESCRIPTION

"Overlap Trailing Green Parameter in seconds (0-255 sec). When this value is greater than zero and the overlap green would normally terminate, the overlap green shall be extended by this additional time."
::= { overlapEntry 5 }

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2.10.2.6 Overlap Trailing Yellow Change Parameter

```
overlapTrailYellow  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Overlap Trailing Yellow Change Parameter in tenth seconds (NEMA range: 3.0-25.5)
            seconds. When the overlap green has been extended (Trailing Green), this value shall
            determine the current length of the Yellow Change interval for the overlap."
::= { overlapEntry 6 }
```

2.10.2.7 Overlap Trailing Red Clear Parameter

```
overlapTrailRed  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-write
        STATUS  mandatory
        DESCRIPTION
            "Overlap Trailing Red Clear Parameter in tenth seconds (0-25.5 sec). When the overlap
            green has been extended (Trailing Green), this value shall determine the current length of
            the Red Clearance interval for the overlap."
::= { overlapEntry 7 }
```

2.10.3 Maximum Overlap Status Groups

```
maxOverlapStatusGroups  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Overlap Status Groups (8 overlaps per group) this Actuated
            Controller Unit supports. This value is equal to TRUNCATE [(maxOverlaps + 7) / 8]. This
            object indicates the maximum rows which shall appear in the overlapStatusGroupTable
            object."
::= { overlap 3 }
```

2.10.4 Overlap Status Group Table

```
overlapStatusGroupTable  OBJECT-TYPE
        SYNTAX  SEQUENCE OF OverlapStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit overlap output (Red, Yellow, & Green) status in
            groups of eight overlaps. The number of rows in this table is equal to the
            maxOverlapStatusGroups object."
::= { overlap 4 }

overlapStatusGroupEntry  OBJECT-TYPE
        SYNTAX  OverlapStatusGroupEntry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "Red, Yellow, & Green Output Status for eight Actuated Controller Unit overlaps."
        INDEX  { overlapStatusGroupNumber }
::= { overlapStatusGroupTable 1 }
```

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```
OverlapStatusGroupEntry ::= SEQUENCE {
        overlapStatusGroupNumber                INTEGER,
        overlapStatusGroupReds                  INTEGER,
        overlapStatusGroupYellows               INTEGER,
        overlapStatusGroupGreens                INTEGER }
```

2.10.4.1 Overlap Status Group Number

```
overlapStatusGroupNumber  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The overlap StatusGroup number for objects in this row. This value shall not exceed the
            maxOverlapStatusGroups object value."
::= { overlapStatusGroupEntry 1 }
```

2.10.4.2 Overlap Status Group Reds

```
overlapStatusGroupReds  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Overlap Red Output Status Mask, when a bit = 1, the Overlap Red is currently active. When
            a bit = 0, the Overlap Red is NOT currently active.
                Bit 7 = Overlap number = (overlapStatusGroupNumber * 8)
                Bit 6 = Overlap number = (overlapStatusGroupNumber * 8) - 1
                Bit 5 = Overlap number = (overlapStatusGroupNumber * 8) - 2
                Bit 4 = Overlap number = (overlapStatusGroupNumber * 8) - 3
                Bit 3 = Overlap number = (overlapStatusGroupNumber * 8) - 4
                Bit 2 = Overlap number = (overlapStatusGroupNumber * 8) - 5
                Bit 1 = Overlap number = (overlapStatusGroupNumber * 8) - 6
                Bit 0 = Overlap number = (overlapStatusGroupNumber * 8) - 7"
::= { overlapStatusGroupEntry 2 }
```

2.10.4.3 Overlap Status Group Yellows

```
overlapStatusGroupYellows  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Overlap Yellow Output Status Mask, when a bit = 1, the Overlap Yellow is currently active.
            When a bit = 0, the Overlap Yellow is NOT currently active.
                Bit 7 = Overlap number = (overlapStatusGroupNumber * 8)
                Bit 6 = Overlap number = (overlapStatusGroupNumber * 8) - 1
                Bit 5 = Overlap number = (overlapStatusGroupNumber * 8) - 2
                Bit 4 = Overlap number = (overlapStatusGroupNumber * 8) - 3
                Bit 3 = Overlap number = (overlapStatusGroupNumber * 8) - 4
                Bit 2 = Overlap number = (overlapStatusGroupNumber * 8) - 5
                Bit 1 = Overlap number = (overlapStatusGroupNumber * 8) - 6
                Bit 0 = Overlap number = (overlapStatusGroupNumber * 8) - 7"
::= { overlapStatusGroupEntry 3 }
```

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2.10.4.4 Overlap Status Group Greens

```
overlapStatusGroupGreens  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "Overlap Green Output Status Mask, when a bit = 1, the Overlap Green is currently active.
            When a bit = 0, the Overlap Green is NOT currently active.
               Bit 7 = Overlap number = (overlapStatusGroupNumber * 8)
               Bit 6 = Overlap number = (overlapStatusGroupNumber * 8) - 1
               Bit 5 = Overlap number = (overlapStatusGroupNumber * 8) - 2
               Bit 4 = Overlap number = (overlapStatusGroupNumber * 8) - 3
               Bit 3 = Overlap number = (overlapStatusGroupNumber * 8) - 4
               Bit 2 = Overlap number = (overlapStatusGroupNumber * 8) - 5
               Bit 1 = Overlap number = (overlapStatusGroupNumber * 8) - 6
               Bit 0 = Overlap number = (overlapStatusGroupNumber * 8) - 7"
::= { overlapStatusGroupEntry 4 }
```

2.11 TS2 PORT 1 PARAMETERS

```
ts2port1  OBJECT IDENTIFIER
::= { asc 10 }

-- This object is an identifier used to group all objects for support of TS 2 port1 activities.
```

2.11.1 Maximum Port 1 Addresses

```
maxPort1Addresses  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Maximum Number of Port 1 addresses this Actuated Controller Unit supports. This
            object indicates the maximum rows which shall appear in the port1Table object."
::= { ts2port1 1 }
```

2.11.2 Port 1 Table

```
port1Table  OBJECT-TYPE
        SYNTAX  SEQUENCE OF Port1Entry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "A table containing Actuated Controller Unit port 1 parameters. The number of rows in this
            table is equal to the maxPort1Addresses object."
::= { ts2port1 2 }

port1Entry  OBJECT-TYPE
        SYNTAX  Port1Entry
        ACCESS  not-accessible
        STATUS  mandatory
        DESCRIPTION
            "This object defines a conceptual row in the port 1 Table."
        INDEX { port1Number }
::= { port1Table 1 }
```

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```
Port1Entry ::= SEQUENCE {
        port1Number             INTEGER,
        port1DevicePresent      INTEGER,
        port1Frame40Enable      INTEGER,
        port1Status             INTEGER,
        port1FaultFrame         INTEGER }
```

2.11.2.1 Port 1 Number

```
port1Number  OBJECT-TYPE
        SYNTAX  INTEGER (0..255)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The Port 1 address for objects in this row. This value shall not exceed the
            maxPort1Addresses object value."
::= { port1Entry 1 }
```

2.11.2.2 Port 1 Device Present

```
port1DevicePresent  OBJECT-TYPE
        SYNTAX  INTEGER (0..1)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "The presence or absence of a device for this port 1 address. Command Frames shall be
            transmitted only to those devices that are present as determined by this programming.  If the
            object is TRUE (non-zero) then the device is present.  If the object is FALSE (zero) then the
            device is not present."
        REFERENCE
            "NEMA TS 2 Clause 3.3.1.4"
::= { port1Entry 2 }
```

2.11.2.3 Port 1 Frame 40 Enable

```
port1Frame40Enable  OBJECT-TYPE
        SYNTAX  INTEGER (0..1)
        ACCESS  read-only
        STATUS  mandatory
        DESCRIPTION
            "To enable or disable Frame 40 messages to the device at this port 1 address. Frame 40 is
            used to poll the secondary stations for a secondary to secondary message exchange.
            Command 40 series frames shall be transmitted only to those devices that are enabled, as
            determined by this programming.
                TRUE (non-zero) - Enable frame 40 messages for this device.
                FALSE (zero) - Disable frame 40 messages for this device."
        REFERENCE
            "NEMA TS 2 Clause 3.3.1.4.1"
::= { port1Entry 3 }
```

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2.11.2.4 Port 1 Status

```
port1Status OBJECT-TYPE
        SYNTAX INTEGER {    other (1),
                            online (2),
                            responseFault (3) }
        ACCESS read-write
        STATUS mandatory
        DESCRIPTION
            "This object indicates the communications status with the associated device:
            online - This indicates that at least five of the most recent 10 response transfers were
                    received correctly
            responseFault - This indicates that more than 5 of the most recent 10 response transfers
                    were received incorrectly.
            other - This indicates that some other communications fault has been detected."
::= { port1Entry 4 }
```

2.11.2.5 Port 1 Fault Frame

```
port1FaultFrame OBJECT-TYPE
        SYNTAX INTEGER  (0..255)
        ACCESS read-only
        STATUS mandatory
        DESCRIPTION
            "This object indicates the frame number that caused the most recent fault."
::= { port1Entry 5 }

END
```

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Section 3
Group Definitions

A Conformance Group is defined in NEMA TS 3.2 Clause 3.3.5.

Conformance Groups are defined as either mandatory or optional. If a Conformance Group is mandatory, all of the objects with STATUS "mandatory" that are part of the Conformance Group shall be present for a device to claim conformance to the Group. If a Conformance Group is optional, all of the objects that are part of the Conformance Group with the STATUS "mandatory" shall be present if the device supports the Conformance Group. Objects with the STATUS "optional" may be supported.

When a table is included in a Conformance Group, all objects contained in the table are included by reference. This is because a table is defined as a SEQUENCE OF {SEQUENCE}. Thus, all objects listed in the sequence are defined as an integral part of the table. Tables are defined as either mandatory or optional. If a table is mandatory, all of the objects with STATUS "mandatory" shall be present. If a table is optional, all of the objects with the STATUS "mandatory" shall be present if the device supports the table. Objects in the table with the STATUS "optional" may be supported.

Table 3-1
OBJECT SUPPORT REQUIREMENTS

Object Status	Table Status	Group Status	Object Support
mandatory	mandatory	mandatory	mandatory
mandatory	mandatory	optional	mandatory, if group is supported
mandatory	optional	mandatory	mandatory, if table is supported
mandatory	optional	optional	mandatory, if both the group and table are supported
optional	mandatory	mandatory	optional
optional	mandatory	optional	optional
optional	optional	mandatory	optional
optional	optional	optional	optional

The Conformance Group definitions for actuated signal controllers are defined in this section. An actuated signal controller has multiple functions; thus, Conformance Groups are defined for each function.

3.1 PHASE CONFORMANCE GROUP

The Phase Conformance Group consists of the phase timing parameters, and phase status variables. The Phase Group shall consist of the following objects:

Object or Group Name	Reference
maxPhases	TS 3.5
phaseTable	TS 3.5
maxPhaseGroups	TS 3.5
phaseStatusGroupTable	TS 3.5

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3.2 DETECTOR CONFORMANCE GROUP

The Detector Conformance Group consists of the detector configuration parameters, and the detector status variables. The Detector Group consists of the following objects:

Object or Group Name	Reference
maxVehicleDetectors	TS 3.5
vehicleDetectorTable	TS 3.5
maxVehicleDetectorStatusGroups	TS 3.5
vehicleDetectorStatusGroupTable	TS 3.5
maxPedestrianDetectors	TS 3.5
pedestrianDetectorTable	TS 3.5

3.3 VOLUME OCCUPANCY REPORT CONFORMANCE GROUP

The Volume Occupancy Report Group shall consist of the following objects:

Object or Group Name	Reference
volumeOccupancySequence	TS 3.5
volumeOccupancyPeriod	TS 3.5
activeVolumeOccupancyDetectors	TS 3.5
volumeOccupancyTable	TS 3.5

3.4 UNIT CONFORMANCE GROUP

The Unit Group consists of objects related to overall controller configuration and state. The Unit Group shall consist of the following objects:

Object or Group Name	Reference
unitStartUpFlash	TS 3.5
unitBackupTime	TS 3.5
unitRedRevert	TS 3.5
unitControlStatus	TS 3.5
unitFlashStatus	TS 3.5
unitAlarmStatus2	TS 3.5
unitAlarmStatus1	TS 3.5
shortAlarmStatus	TS 3.5
unitControl	TS 3.5
maxAlarmGroups	TS 3.5
alarmGroupTable	TS 3.5

3.5 SPECIAL FUNCTION CONFORMANCE GROUP

The Special Function Conformance Group consists of those objects related to control of special function outputs.

Object or Group Name	Reference
maxSpecialFunctionOutputs	TS 3.5
specialFunctionOutputTable	TS 3.5

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3.6 COORDINATION CONFORMANCE GROUP

The Coordination Group consists of those objects related to signal coordination. The Coordination Group shall consist of the following objects:

Object or Group Name	Reference
coordOperationalMode	TS 3.5
coordCorrectionMode	TS 3.5
coordMaximumMode	TS 3.5
coordForceMode	TS 3.5
maxPatterns	TS 3.5
patternTableType	TS 3.5
patternTable	TS 3.5
maxSplits	TS 3.5
splitTable	TS 3.5
coordPatternStatus	TS 3.5
localFreeStatus	TS 3.5
coordCycleStatus	TS 3.5
coordSyncStatus	TS 3.5
systemPatternControl	TS 3.5
systemSyncControl	TS 3.5

3.7 TIME BASE CONFORMANCE GROUP

The Time Base Group consists of the asc specific objects related to time base operation. The Time Base Group shall consist of the following objects:

Object or Group Name	Reference
Time Management Conf. Group	TS 3.4
timebasePatternSync	TS 3.5
maxTimebaseAscActions	TS 3.5
timebaseAscActionTable	TS 3.5
timebaseAscActionStatus	TS 3.5

3.8 PREEMPT CONFORMANCE GROUP

The Preempt Group consists of the preempt configuration parameters, and the preempt status variables. The Preempt Conformance Group shall consist of the following objects:

Object or Group Name	Reference
maxPreempts	TS 3.5
preemptTable	TS 3.5

3.9 RING CONFORMANCE GROUP

The Ring Group consists of the ring configuration parameters, status variables. The Ring Conformance Group shall consist of the following objects:

Object or Group Name	Reference
maxRings	TS 3.5
maxSequences	TS 3.5
sequenceTable	TS 3.5

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3.10 CHANNEL CONFORMANCE GROUP

The Channel Group consists of the channel configuration parameters, and status variables. The Channel Group shall consist of the following objects:

Object or Group Name	Reference
maxChannels	TS 3.5
channelTable	TS 3.5
maxChannelStatusGroups	TS 3.5
channelStatusGroupTable	TS 3.5

3.11 OVERLAP CONFORMANCE GROUP

The Overlap Group consists of the overlap configuration parameters, and status variables. The Overlap Group shall consist of the following objects:

Object or Group Name	Reference
maxOverlaps	TS 3.5
overlapTable	TS 3.5
maxOverlapStatusGroups	TS 3.5
overlapStatusGroupTable	TS 3.5

3.12 TS-2 PORT1 CONFORMANCE GROUP

The TS-2 Port1 Conformance Group consists of the TS-2 port 1 configuration parameters, status variables, and control objects. The TS-2 Group shall consist of the following objects:

Object or Group Name	Reference
maxPort1Addresses	TS 3.5
port1Table	TS 3.5

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Section 4
CONFORMANCE STATEMENTS

Actuated Signal Controller (ASC) devices shall adhere to the conformance requirements specified in Table 4-1 as a minimum to claim compliance to this standard. Additional objects or groups may be supported without being non-compliant with ASC objects or NTCIP.

Minimum and maximum ranges of objects that differ from the values of the object's SYNTAX field may be enforced by an application running on a device.

A device which enforces range limits within the bounds specified by the values of the object's SYNTAX field shall not be categorized as being non-compliant with ASC objects or NTCIP.

A device which supports a subset of objects with enumerated values shall not be categorized as being non-compliant with ASC objects or NTCIP.

Table 4-1
CONFORMANCE TABLE

Conformance Group	Reference	Conformance Requirement
Configuration	TS 3.4	mandatory
Database Management	TS 3.4	optional
Time Management	TS 3.4	optional
Timebase Event Schedule	TS 3.4	optional
Report	TS 3.4	optional
STMP	TS 3.4	optional
PMPP	TS 3.4	optional
Phase	TS 3.5	mandatory
Detector	TS 3.5	mandatory
Volume Occupancy Report	TS 3.5	optional
Unit	TS 3.5	optional
Special Function	TS 3.5	optional
Coordination	TS 3.5	optional
Time Base	TS 3.5	optional
Preempt	TS 3.5	optional
Ring	TS 3.5	optional
Channel	TS 3.5	optional
Overlap	TS 3.5	optional
TS 2 Port 1	TS 3.5	optional

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