

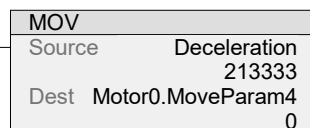
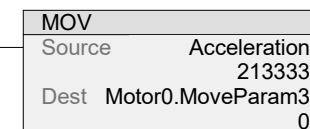
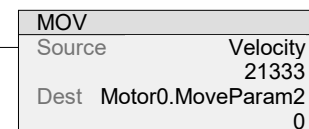
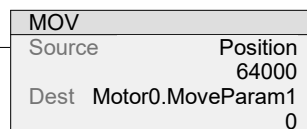
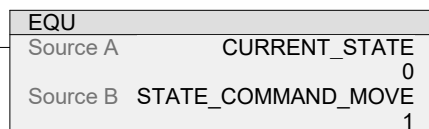
=====

COMMAND MOVE

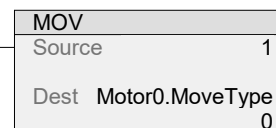
=====

Set all parameters for a position move, including position, velocity, acceleration, the move type, and increment the move number to start the move. The move number value should be stored locally so it can be used to detect if the move is interrupted later in the routine.

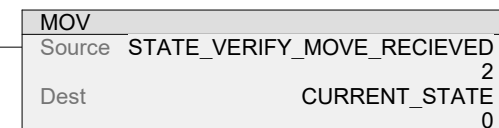
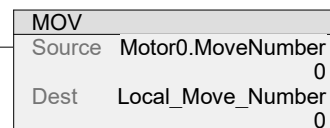
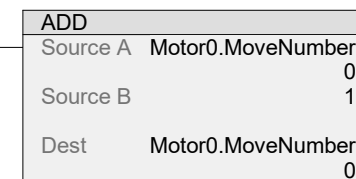
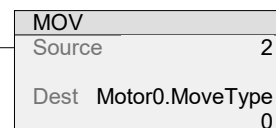
MAM_Active



Position_Target_Is_Absolute



Position_Target_Is_Absolute



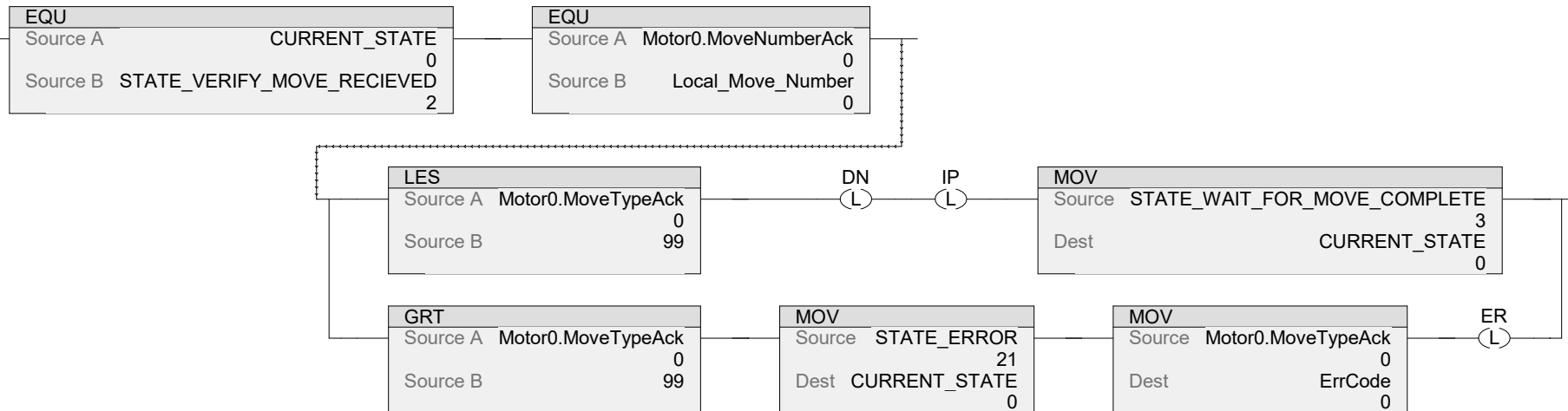
=====

VERIFY MOVE RECIEVED

=====

Monitor the move number ack and wait for it to equal the move number used to start the move. This will indicate the motor has received the move command. Once it has been verified that the motor has received the move, check the move type ack to confirm the move was accepted. If the motor is unable to start the move, it will return a move type error (MoveTypeAck greater than 99). If a move type error has occurred, set the error code equal to the move type error.

2



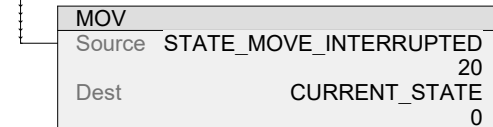
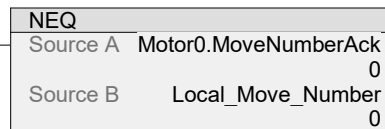
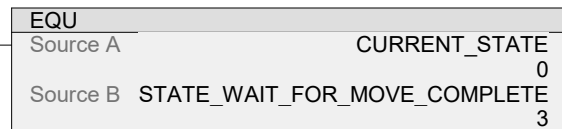
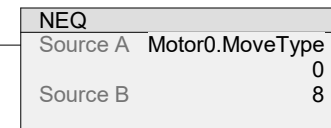
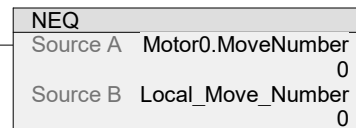
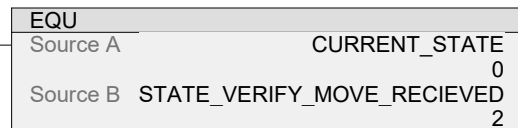
=====

CHECK FOR INTERRUPTIONS

=====

Monitor conditions that would indicate the move has been interrupted. If the move number set by this routine is modified or the move number ack is changed after the move has been started, transition to the move interrupted state and unlatch the IP progress output to indicate that this move has stopped executing.

3

IP
U

