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Gantry

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- Gantry
- Command Position, Feedback Position
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- Position Monitor
 - "F.Position.PreCorrection"
 - "C.Position.PreCorrection"
 - "F.Position.PreCorrection"
 - Position Count
 - "C.Count.PreCorrection",
 - "F.Count.PreCorrection"
- Command Position
- Feedback Position

Position Monitor				
Reset	C.Position	<div><div>✓</div>C.Position</div>	F.Speed	Torque
Axis 0	200 000	<div><div>▼</div>F.Position</div>	0	- 8.70
Axis 1	200 000	<div><div>✓</div>C.Count</div>	0	8.90
Axis 2	0	<div><div>✓</div>F.Count</div>	- 2	0.00
		<div><div>✓</div>C.Speed</div>		
		<div><div>✓</div>F.Speed</div>		
		<div><div>✓</div>Torque</div>		
		C.Position.Motor		
		F.Position.Motor		
		C.Position.PreCorrection		
		F.Position.PreCorrection		
		C.Count.Motor		
		F.Count.Motor		
		C.Count.PreCorrection		
		F.Count.PreCorrection		

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Position Monitor							
Reset	C.Position	F.Position	C.Speed	F.Speed	Torque	C.Pos.Pre Corr	F.Pos.PreC orr
Axis 0	100 000	100 000	0	- 7	- 8.30	100 000	100 000
Axis 1	100 000	100 000	0	0	3.20	99 900	99 900
Axis 2	0	- 2	0	2	0.00	0	- 2

comizoa, , ide, ethercat, gantry, , ,

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