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Gantry

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

Position Monitor

Reset	C.Position	F.Position	F.Speed	Torque
Axis 0	200 000		0	- 8.70
Axis 1	200 000		0	8.90
Axis 2	0		- 2	0.00

- ▼ C.Position
- ▼ F.Position
- C.Count
- F.Count
- ▼ C.Speed
- ▼ F.Speed
- ▼ Torque
- 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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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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