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2.2.1 Important Motor Settings

2.3 Testing with a m

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3.2 Reply F

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P.2267521Sv DPDc[(1F-8(mwET 248.69 0 0 1 56.64[52.656751.5[D)] TJ ET 528.70 0 1 1 56.642810136751.5[D)] TJcoPDmmPDndc[(2(sc[(PDis] 2[

3.4.4 Control Commands

These commands are used to control the program flow (loops, conditions, jumps etc.). *It does not make sense to use them in direct mode. They are intended for standalone mode only.*

3.4.6 Interrupt C

3.6 The ASCII Interface

3.7.3 MST (motor stop)

With this command the motor will be instructed to stop. The command uses the normal acceleration

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3.7.10

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3.7.16 CALC (calculate)

3.7.17 COMP (compare)

The specified number is compared to the value in the accumulator register. The result of the comparison can

3.7.23 STOP (stop TMCL program execution)

3.7.31 CLE (clear error flags)

This command clears the internal error flags. *It is intended for use in standalone mode only and must not be used in direct mode.*

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PD-18ui2y./ TMCM 0 Tc[(-)] TJ ET BT126.020 1 71.064 810m 0 Tc[(-)] TJ ET BT128.780 1 71.064 810.96 Tm [(1)-5(8ui2y.T)4(M

Number	Axis Parameter

5 Global Parameters

GLOBAL PARAMETERS ARE GROUPED INTO

6 Hints and T

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