

Simple Step

Quick Reference Guide for the Windows Application

	Address	Command	Loop
1	1	A5000A0R	
2	End		

This example will make motor #1 go to Absolute Position 5000, then back to Absolute position 0.

Useful Commands:

- P5000 run motor in the positive direction for 5000 steps
- D5000 run motor in the negative direction for 5000 steps
- A5000 moves motor to Absolute Position to 5000
- A0 moves motor back to Absolute position 0
- M500 waits for 500 milliseconds
- T terminates the current command
- z0 sets the current position to 0 (Note: you cannot move in the negative direction now)
- Z5000 sets the current position to 5000 steps away from 0
- I50 sets the current to 50% of the max. current
- h50 sets the holding current to 50% of the max. current
- j2 sets the step resolution to be half stepping
- v200 sets the starting velocity to be 200 pps
- V5000 sets the top velocity to be 5000 pps

Loops: (Case Sensitive)

1	1	A5000A0R	
2	Loop	1	5
3	End		

This will run line 1, five times.

Wait statements, and the 'W' command:

1	1	A5000A0R	W
2	2	A5000A0R	W
3	Wait	5	
4	End		

This will execute line 1 first, and line 2 will not execute until line 1 has finished. Then the program will wait for 5 milliseconds.

Goto statement:

1	1	A5000A0R	W
2	Goto	1	
3	End		

This will execute line 1, then it will continuously execute line 1 until you click 'End'