odrv0.axis1.requested\_state = AXIS\_STATE\_MOTOR\_CALIBRATION

odrv0.axis1.motor.config.pre\_calibrated = True

odrv0.axis1.requested\_state = AXIS\_STATE\_ENCODER\_HALL\_POLARITY\_CALIBRATION

odrv0.axis1.requested\_state = AXIS\_STATE\_ENCODER\_OFFSET\_CALIBRATION

odrv0.axis1.encoder.config.pre\_calibrated = True

odrv0.axis1.requested\_state = AXIS\_STATE\_CLOSED\_LOOP\_CONTROL

odrv0.axis1.controller.input\_vel = 0