

Power-Supply	60 W
Model	PSAA-60 W
Input	100-240 VAC
Output	24 VDC, 2.5A
Baudrate	19200
Version	Type I
Driver	<input checked="" type="checkbox"/> 1.2A
Serial Nr. (Controller)	1105-1685
Version (Firmware)	4.20
Axisnumber (address)	2
Configured for	RS-40, VSS25 UHVG Gear 7:1
max.speed	0.9% ^s defined by the motor

Actual settings:

```

Settings for Axis.: %#   Current axis-No.: 2
Serialnumber..... : 11051685
Version.....       : 4 2 0
Options.....       : 0
Status.....        : 0
Position.....      : 0.000000
Switch-Status..... : 0 0
Limits.....        : 0.000000 1000.000000
Error.....         : 0
Stack.....         : 0
1 % setaxis
0.5714 % setpitch
0.900000 % snv
7.500 % sna
80.000 % setnstopdecel
0.900000 1 % setncalvel
0.100000 2 % setncalvel
0.900000 1 % setnrmvel
0.100000 2 % setnrmvel
0.000000 % setncalswdist
2400 % setumotmin
20 % setumotgrad
1 0 % setsw
2 1 % setsw
0 % setmotiondir
-1000.000000 1000.000000 % setinilimit

```

The limit reverse (cal-switch) is active. If switch is active you are not allowed to cross the switch in negative direction! It's a good idea, to deactivate the switch after the homing (cal command), then you are able to move over the switch. But please note, after homing (cal command) the smallest position is 0.000! (the positioning limits are 0.000 to 1000.000 °(command [axisno] getnlimit))

If homing not necessary, deactivate the switch permanently!

2 0 [axisno] setsw
[axisno] nsave