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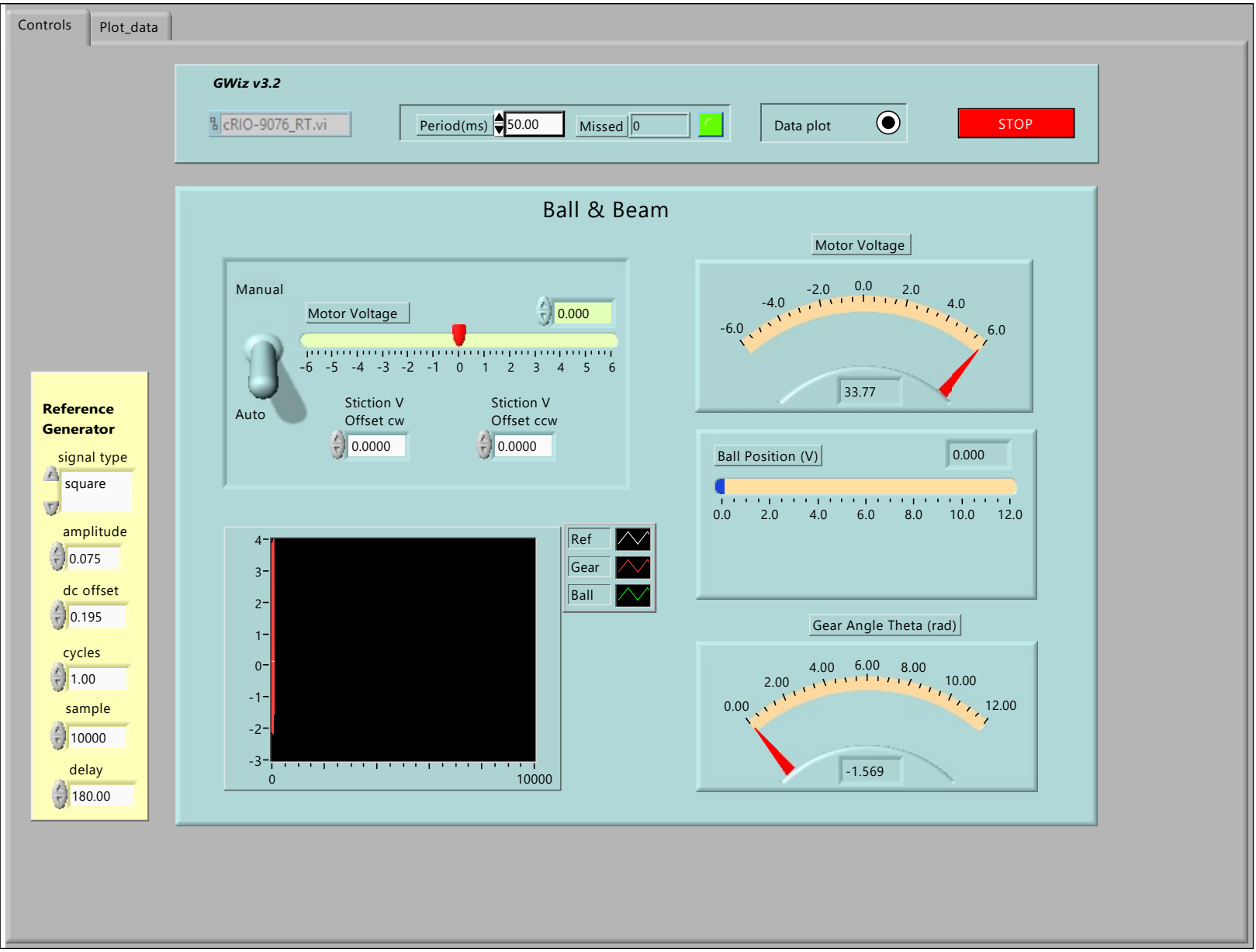
This VI shows an example of how to implement a closed loop position move using the NI 9505. The position loop is implemented using PID. The output of the loop is used as the command for the current loop, which then sets the PWM duty cycle for the motor. This example assumes that an encoder is connected for position and velocity feedback. This example does not implement advanced motion features such as trajectory generation and splining.



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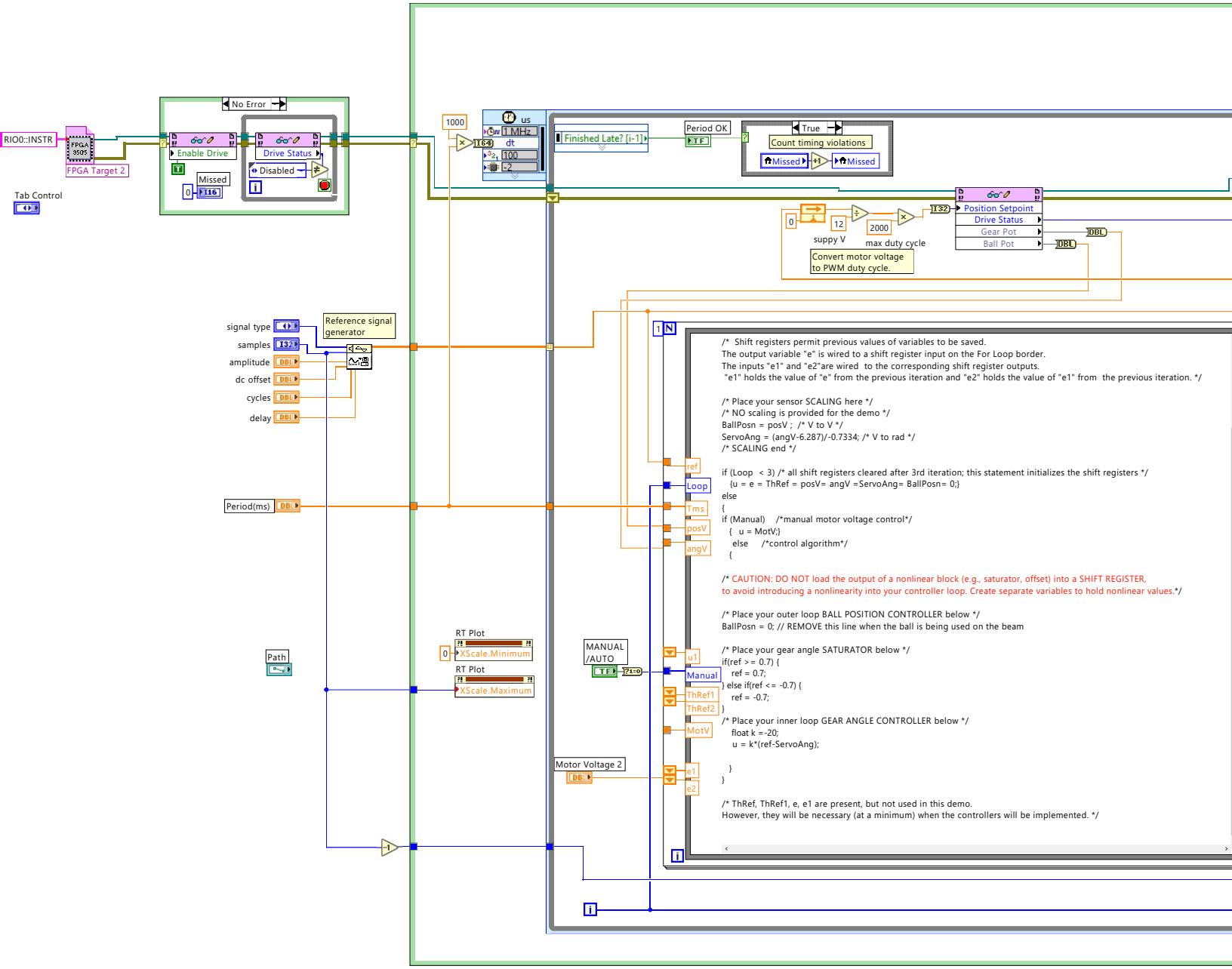

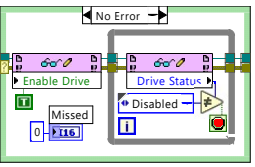

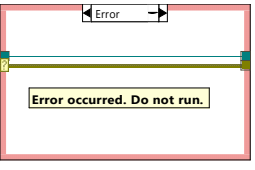

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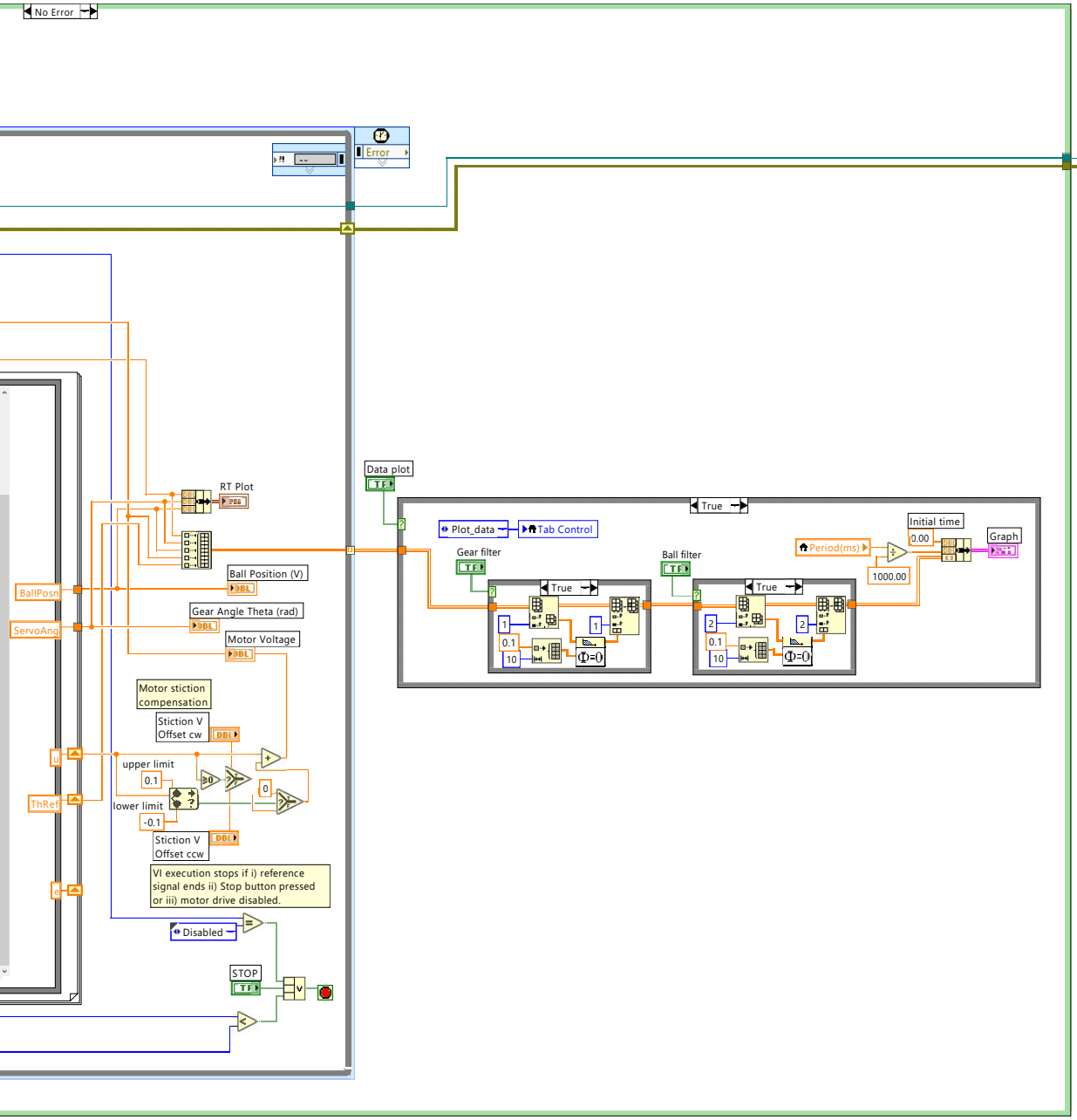

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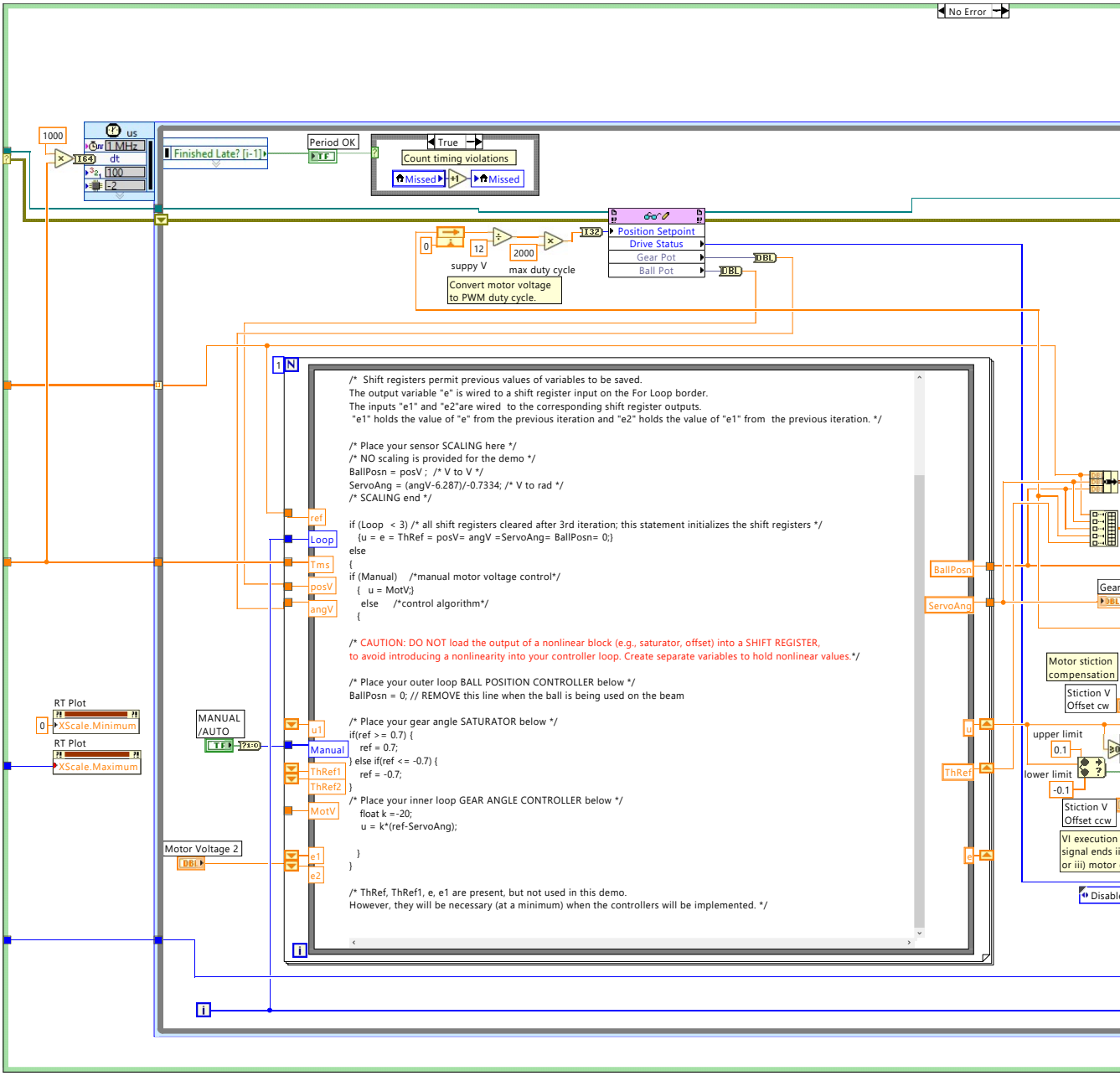

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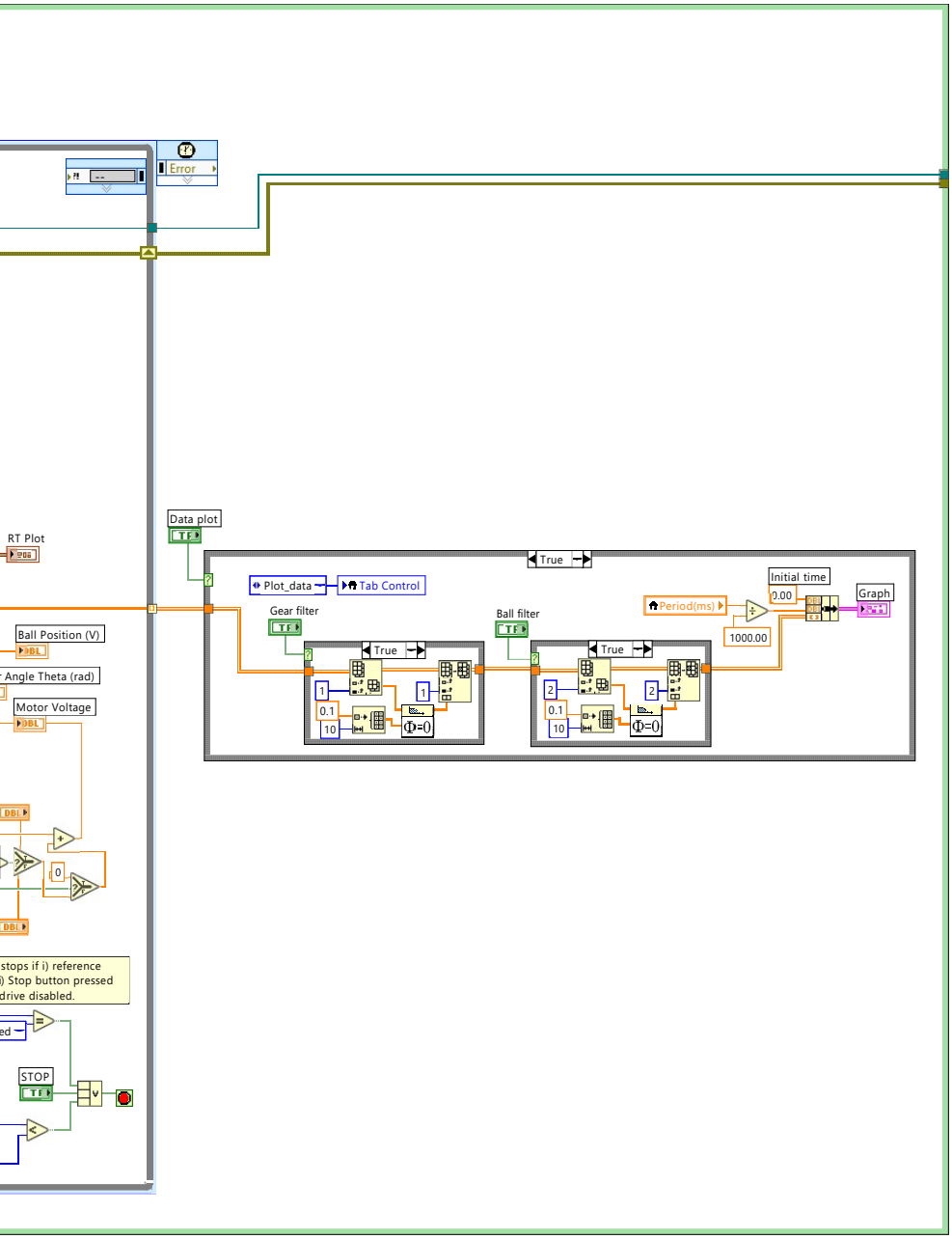

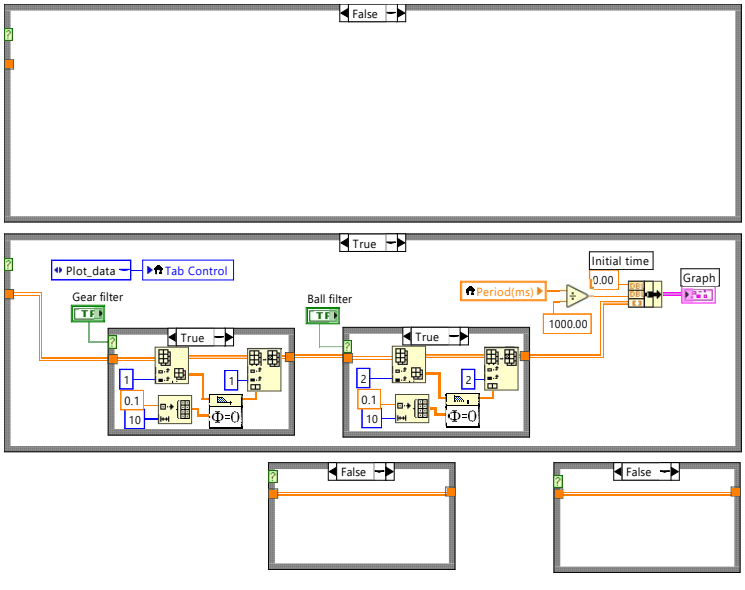

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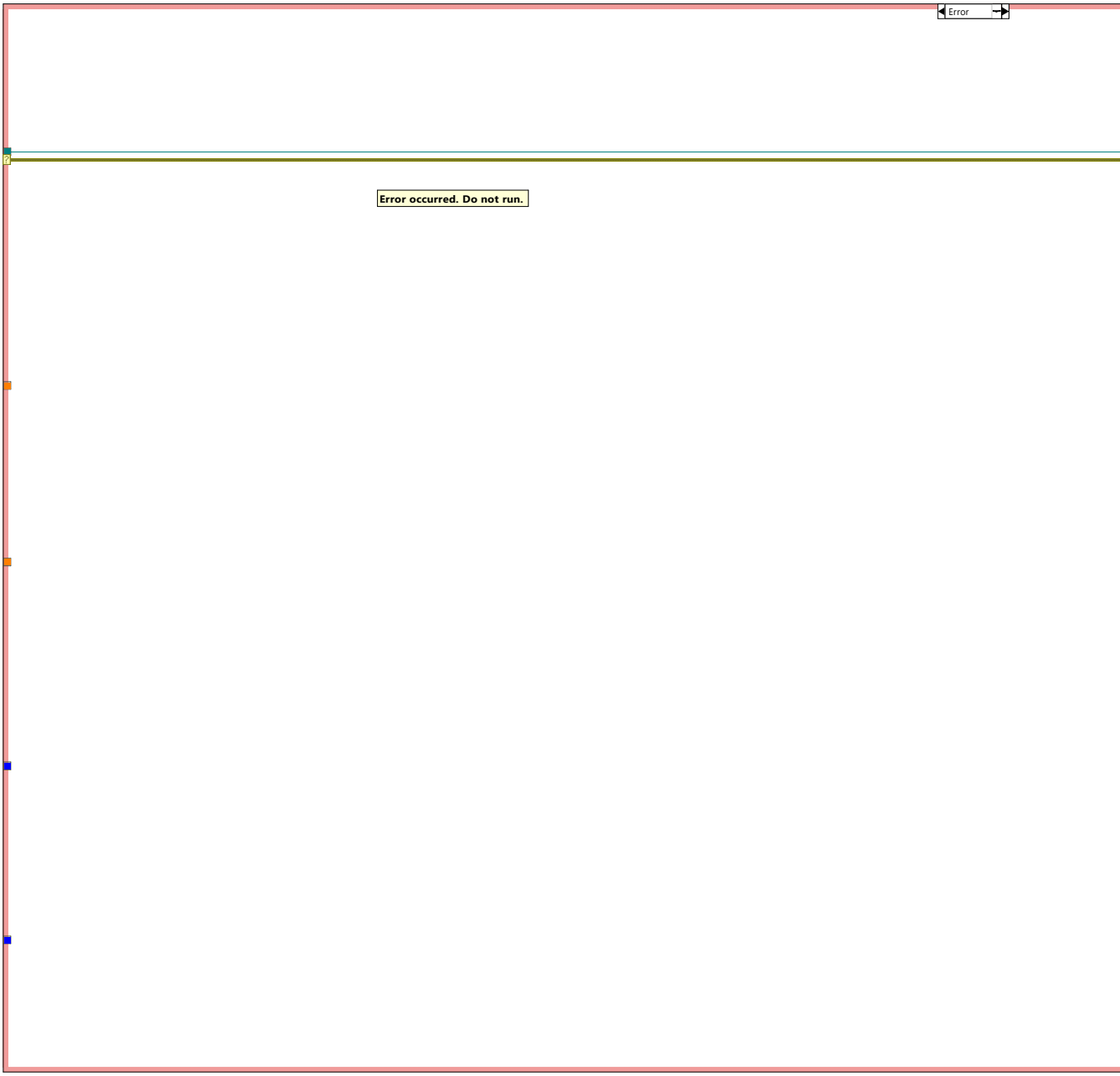

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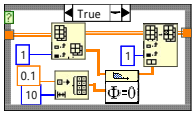

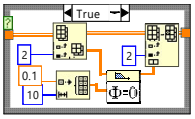

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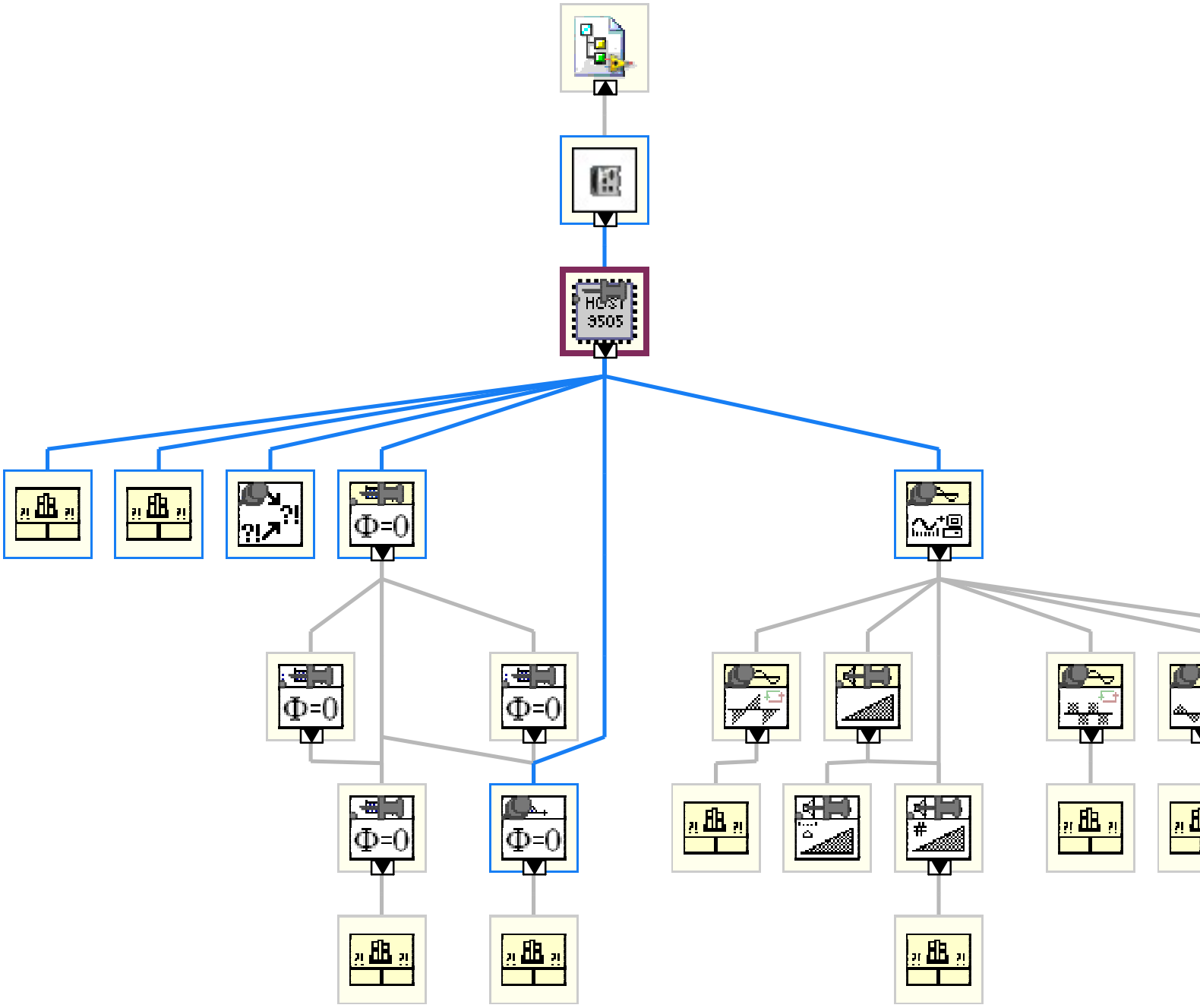

Error Cluster From Error Code.vi
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NI_AALBase.lvlib:Zero Phase Filter (DBL).vi
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NI_AALBase.lvlib:Zero Phase Filter.vi
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NI_AALPro.lvlib:Signal Generator by Duration.vi
C:\Program Files (x86)\National Instruments\LabVIEW 2019\vi.lib\Analysis\0measdsp.llb\Signal Generator by Duration.vi

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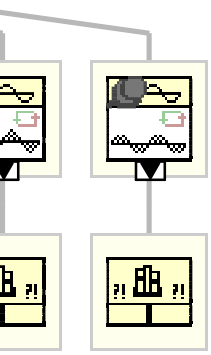

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"cRIO-9076_RT.vi History"
Current Revision: 603
rev. 496 Sep 18, 2017 4:05:16 PM kluscott
v3.2 - Sept.18,2017 integrated plot_data into tab on front panel.