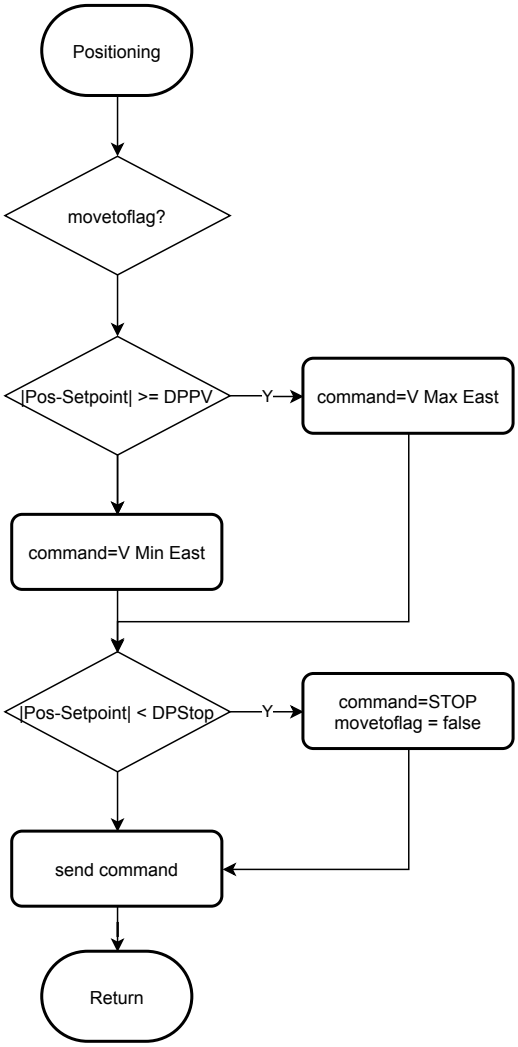


MOVETO

If a goto command is issued the

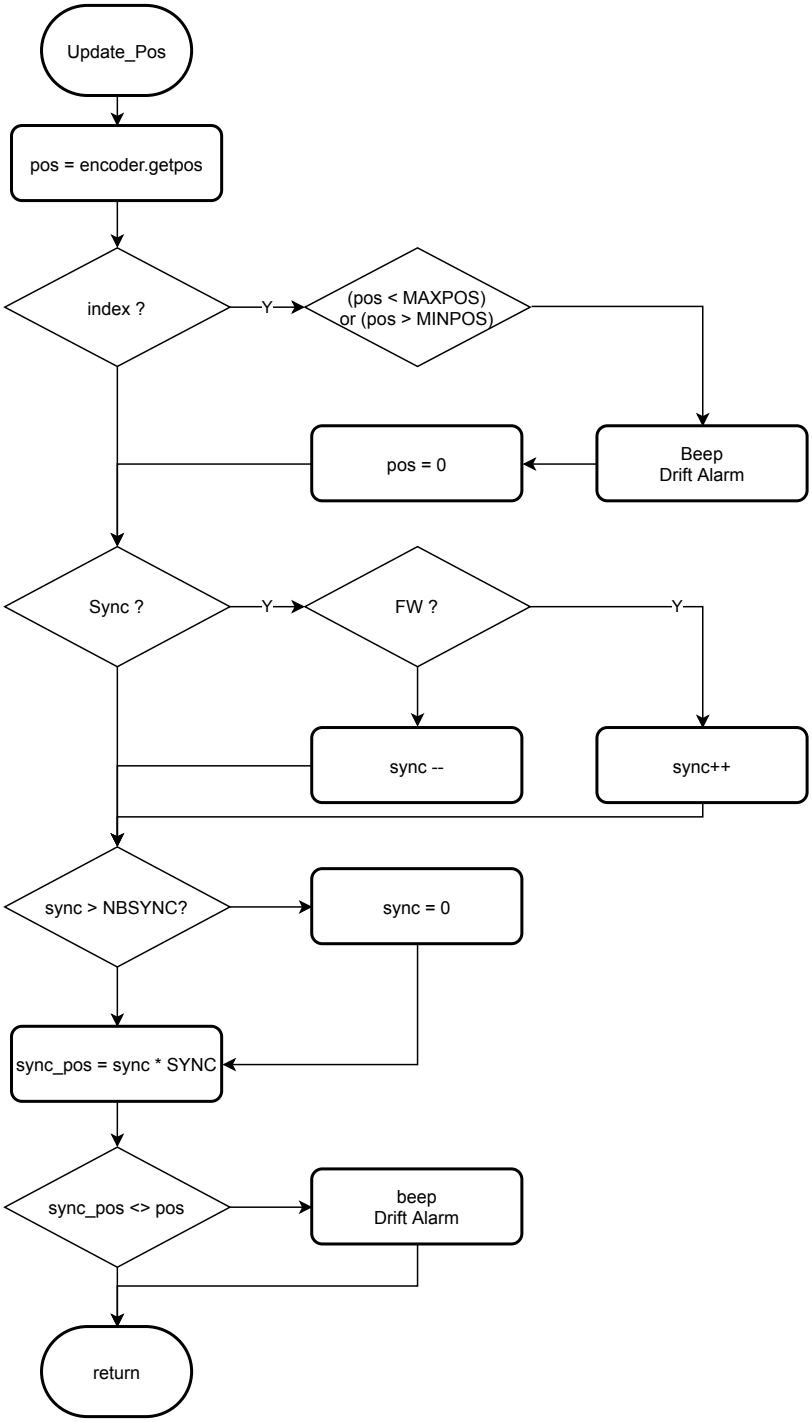
movetoflag is set.

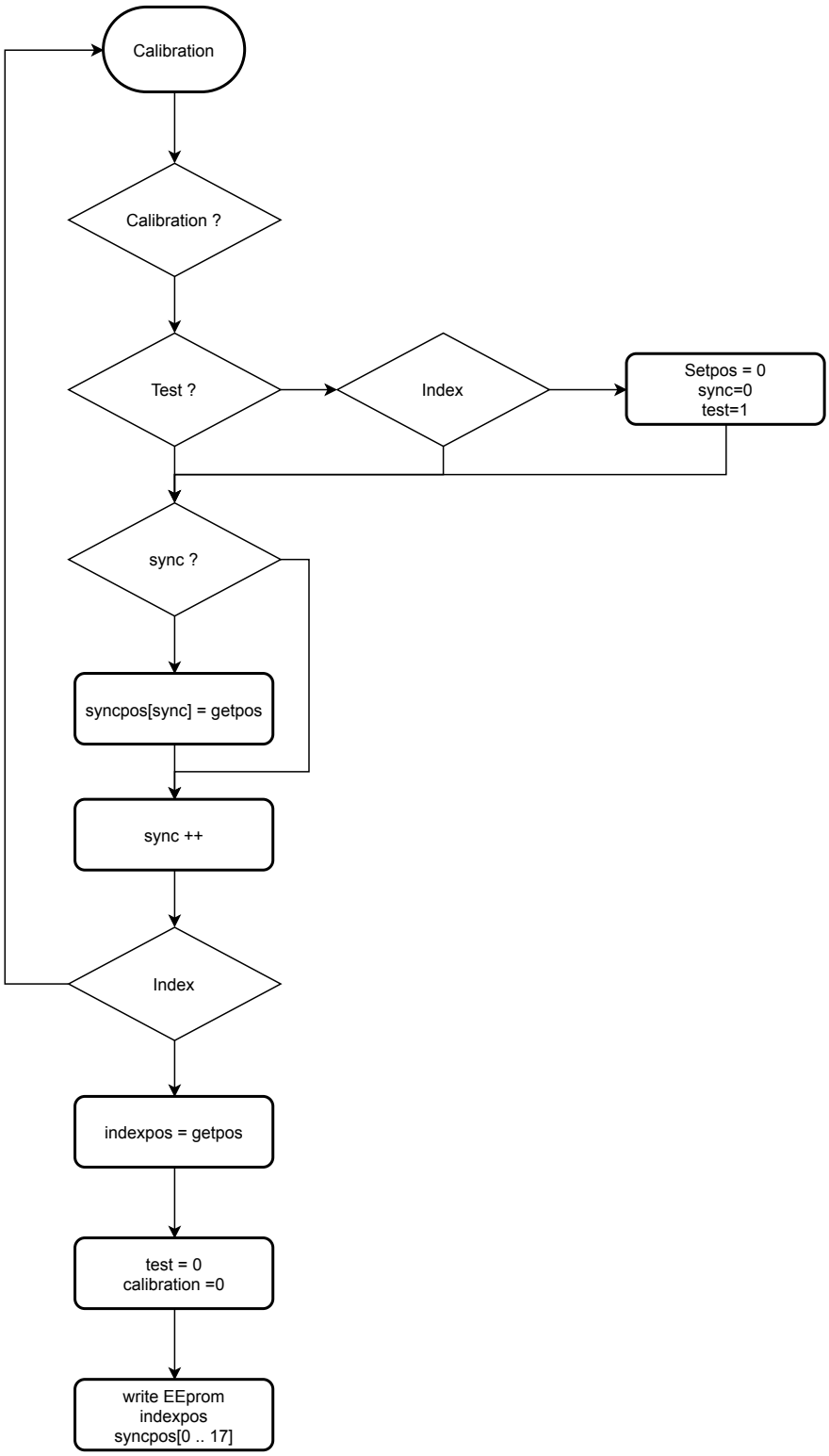
then depending on absolute difference between setpoint and position, the speed is adjusted to

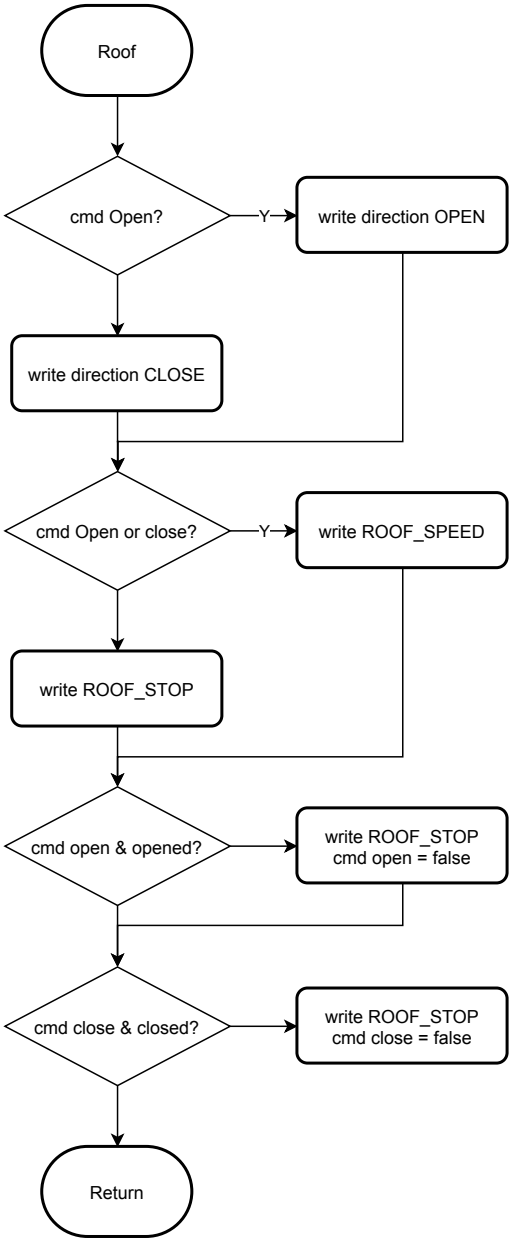
VMAX_E (max speed to east)

VMIN_E (min speed to east)

STOP (stopp movement


Update_Pos
pos = encoder.getpos
index ?
Y
(pos < MAXPOS)
or (pos > MINPOS)
Beep
Drift Alarm
pos = 0
Sync ?
Y
FW ?
Y
sync --
sync++
sync > NBSYNC?
sync = 0
sync_pos = sync * SYNC
sync_pos <> pos
beep
Drift Alarm
return


Calibration
Calibration ?
Test ?
Index
Setpos = 0
sync=0
test=1
sync ?
syncpos[sync] = getpos
sync ++
Index
indexpos = getpos
test = 0
calibration =0
write EEprom
indexpos
syncpos[0 .. 17]



ROOF

If a roof open or close command is set, writes direction accordingly

if either open or close command is set, write the speed to ROOF_SPEED

if not write ROOF_STOP

if a command is set and limit switch is reached, write ROOF_STOP