## Motor Drive Control Algorithm - Runs every 500 uSec Fwd: +Angle Rev: -Angle Stop: 0 (zero) (input variable: tgt\_incre) Yes: decide work based on request and current state No: handle change in speed and/or direction No: just work on current request No: handle change in direction Yes: handle change No: keep motor moving In SPIN\_UP This block adjusts the output of this loop which is the input to the faster Add Uplncr to Dvrlncr Sub DnIncr fm DvrIncr Sub Dnincr fm Dvrincr Sub DnIncr fm DvrIncr motor move loop causing the motor actually move. Set Dvrincr = tgtincr Set Dvrlncr = tgtlncr Set Dyrlncr = 0 Set DvrIncr = 0 Now we are slowed, Let's ramp up to new direction!

(output variable: angle)

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