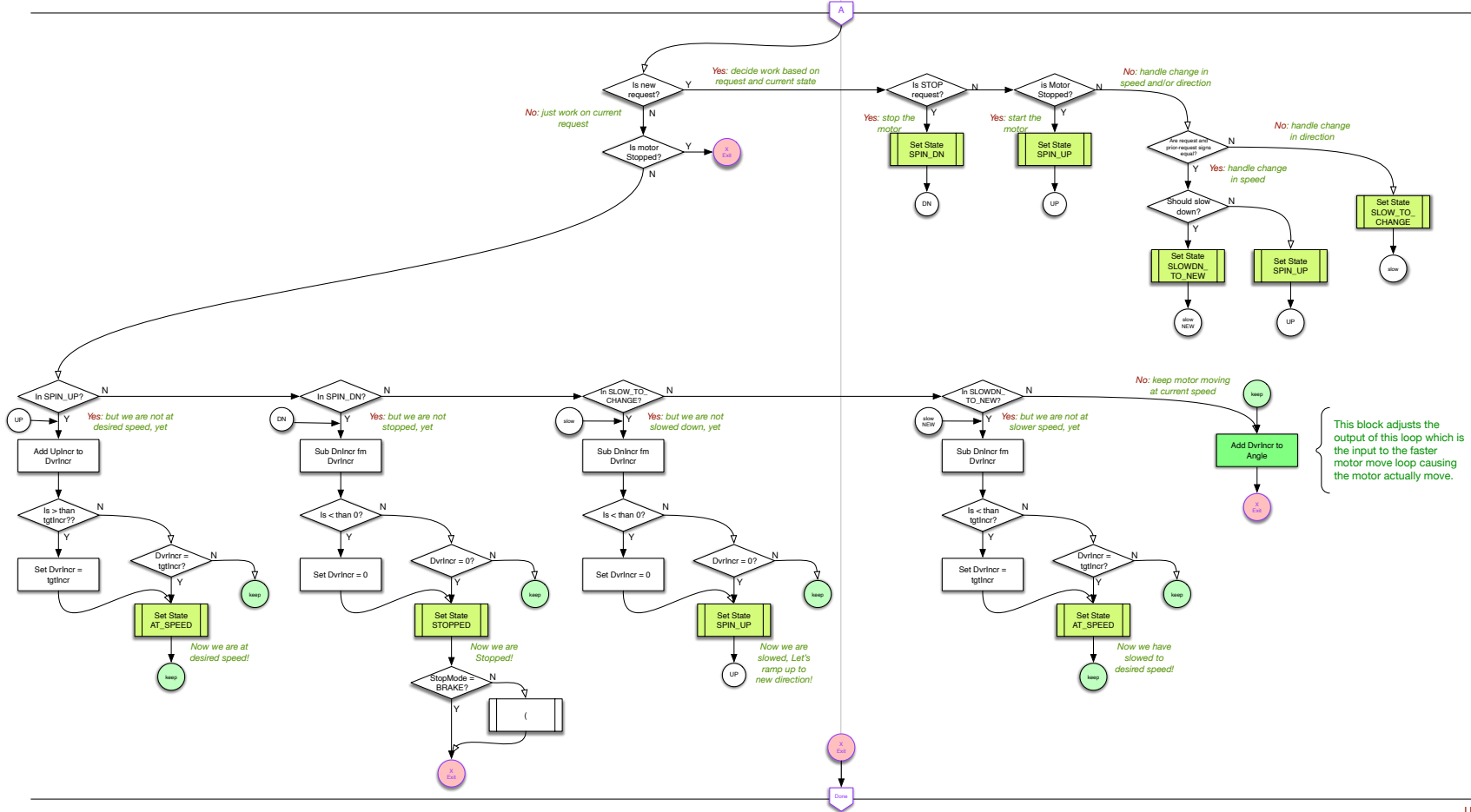


# Motor Drive Control Algorithm - Runs every 500 uSec

Fwd: +Angle  
Rev: -Angle

Stop: 0 (zero)

(input variable: tgt\_incr)



(output variable: angle)