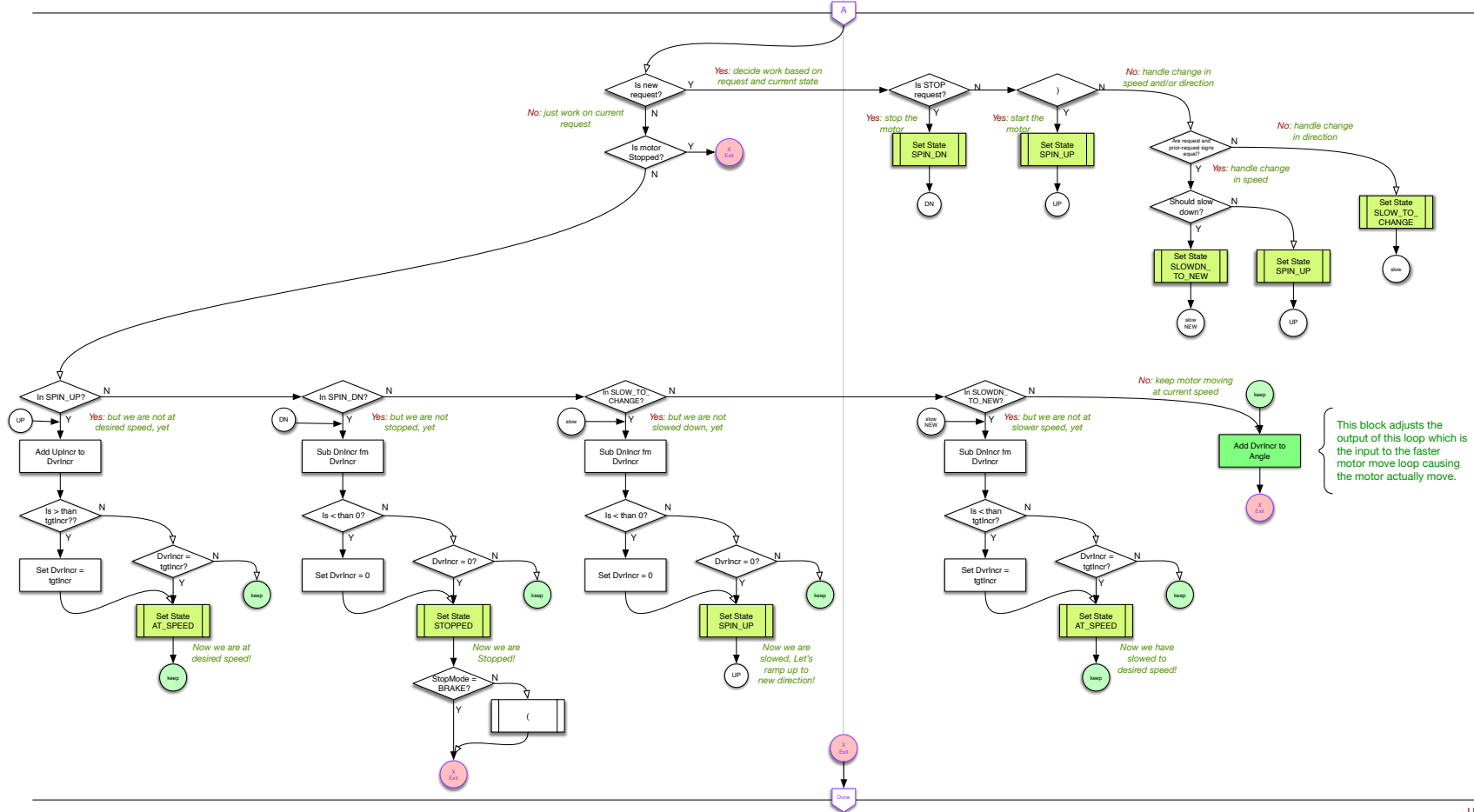


Motor Drive Control Algorithm - Runs every 500 uSec

Fwd: +Angle
Rev: -Angle

Stop: 0 (zero)

(input variable: **tgt_incr**)



This block adjusts the output of this loop which is the input to the faster motor move loop causing the motor actually move.