



t.start: io\_write\_ctrl\_motor\_v\_cmd\_tStart(1,1)

dx\_max: io\_write\_ctrl\_motor\_v\_cmd\_val\_norm\_dx\_max(1,1)  
dx\_min: io\_write\_ctrl\_motor\_v\_cmd\_val\_norm\_dx\_min(1,1)

io\_write\_ctrl\_motor\_v\_cmd\_val\_x(1,1)