Motor interface

get\_constraints(self):

move\_rel(self, param\_dict):

move\_abs(self, param\_dict):

abort(self):

get\_pos(self, param\_list=None):

get\_status(self, param\_list=None):

calibrate(self, param\_list=None):

get\_velocity(self, param\_list=None):

set\_velocity(self, param\_dict):

motor\_stage\_pi\_usb\_gcs2

on\_activate(self):

on\_deactivate(self):

get\_constraints(self):

move\_rel(self, param\_dict):

move\_abs(self, param\_dict):

abort(self):

get\_pos(self, param\_list=None):

get\_status(self, param\_list=None):

calibrate(self, param\_list=None):

get\_velocity(self, param\_list=None):

set\_velocity(self, param\_dict):

\_do\_move\_abs(self, axis, channel, to\_pos):

\_write\_axis\_move(self, axis, channel, to\_pos):

\_set\_servo\_state(self, to\_state):

Magnet\_motor\_interfuse, magnet\_dummy

def on\_activate(self):

def on\_deactivate(self):

def get\_constraints(self):

def move\_rel(self, param\_dict):

def move\_abs(self, param\_dict):

def abort(self):

def get\_pos(self, param\_list=None):

def get\_status(self, param\_list=None):

def calibrate(self, param\_list=None):

def get\_velocity(self, param\_list=None):

def set\_velocity(self, param\_dict=None):

def tell(self, param\_dict=None):

def ask(self, param\_dict=None):

def initialize(self):

def set\_magnet\_idle\_state(self, magnet\_idle=True):

def get\_magnet\_idle\_state(self):

magnet interface

def get\_constraints(self):

def move\_rel(self, param\_dict):

def move\_abs(self, param\_dict):

def abort(self):

def get\_pos(self, param\_list=None):

def get\_status(self, param\_list=None):

def calibrate(self, param\_list=None):

def get\_velocity(self, param\_list=None):

def set\_velocity(self, param\_dict=None):

def tell(self, param\_dict=None):

def ask(self, param\_dict=None):

def initialize(self):

def set\_magnet\_idle\_state(self, magnet\_idle=True):

def get\_magnet\_idle\_state(self):