GT6 Commands and Capabilities

In addition to the Gemini GT drive configuration commands, the Gemini GT6 includes the following motion control commands:

Motion

A	Acceleration
AA	Average Acceleration
AD	Deceleration
ADA	Average Deceleration
CMDDIR	Commanded Direction Polarity
D	Distance
GO	Initiate Motion
K	Kill Motion
S	Stop Motion
V	Velocity
VF	Final Velocity

Homing/Limit

HOM	Go Home
HOMA	Home Acceleration
HOMBAC	Home BackUp Enable
HOMDF	Home Final Direction
HOMEDG	Home Reference Edge
HOMV	Home Velocity
HOMVF	Home Final Velocity
HOMZ	Home to Encoder Z-Channel
LS	Software Limit Enable
LSAD	Software Limit Deceleration
LSADA	Software Limit Average Deceleration
LHAD	Hardware Limit End-of-Travel Deceleration
LHADA	Hardware Limit End-of Travel Average Deceleration
LSNEG	Software EOT Limit – Negative Travel Range
LSPOS	Software EOT Limit – Positive Travel Range

Program Flow

C	Continue
COMEXC	Continue Command Processing Mode
COMEXL	Continue Execution on Limit
COMEXR	Continue Motion on Pause/Continue
COMEXS	Continue Execution on Stop
ELSE	Else Condition for IF Statement
ERROR	Error Checking Enable
GOSUB	Branch to Subroutine
GOWHEN(T)	Go Statement Based on a Time Delay
IF(AS)	If Conditional based on Axis Status
IF(ASX)	If Conditional based on Extended Axis Status
IF(ER)	If Conditional based on Error Status
IF(IN)	If Conditional based on Input Status
IF(SS)	If Conditional based on System Status
JUMP	Jump to Program, No Return
L	Loop
LN	End of Loop
MA	Mode Absolute
MC	Mode Continuous
NIF	End of IF Statement
PRUN PROF	Run a Compiled Profile
PS	Pause Program Execution
RUN PROG	Run a Stored Program
T	Time Delay
TRACE	Program Trace Mode Enable
TRGFN	Trigger Functions
TRGLOT	Trigger Interupt Lockout Time
WAIT(AS)	Wait for Axis Status
WAIT(ASX)	Wait for Extended Axis Status
WAIT(IN)	Wait for Input Status
XONOFF	Enable or Disable XON/XOFF

DisplayTransfer

TACC	Display Commanded Acceleration Set Point
TERRLG	Display Error Log
TMEM	Display Memory Usage
TPROG	Display Contents of Program

Compiled Motion

A	Acceleration
AD	Deceleration
D	Distance
DEF PROF	Define Profile
DEL PROF	Delete Profile
END	End Definition of Program
GOBUF	Store a Motion Segment in Compiled Memory
GOWHEN(T)	Go Statement Based on a Time Delay
MC	Mode Continuous
POUTA	Output State, Compiled
PRUN PROF	Run a Compiled Profile
SGENB	Enable a Servo Gain Set
V	Velocity
VF	Final Velocity

Registration

RE	Registration Enable
REG	Registration Distance
REGLOD	Registration Lock-Out Distance

Inputs/Outputs

INFNC	Input Function Assignment
INSELP	Program Selection with Inputs, Enable
OUT	Set Output State
OUTFNC	Output Function Assignment

Program/Profile Definition

DEF PROG	Define a Program
DEF PROF	Define a Profile
DEL PROG	Delete a Program
DEL PROF	Delete a Profile
END	End of Program or Profile
ERRORP	Assign Error-handling Program
PRUN PROF	Run a Profile
RUN PROG	Run a Program
STARTP	Assign Startup Program