Encoder
Scaled to give
1 /rev

orient-pid.enable
orient-pid.feedback
orient-pid.command
Orient-pid.output

orient.angle
orient.mode
orient.enable
orient.position
orient.command

scale.1.in
scale.1.gain
scale.1.offset
scale.1.out

Set to get suitable motor speed

hm2_5i25.0.encoder.02.reset
hm2_5i25.0.encoder.02.input-index
hm2_5i25.0.encoder.02.position

Near.0.in1
Near.0.in2
Near.0.out

Timedelay.0.in
Timedelay.0.out

and2.1.in0
and2.1.in1
and2.1.out

motion.spindle-at-speed
motion.spindle-brake
motion.spindle-forward
motion.spindle-index-enable
motion.spindle-inhibit
motion.spindle-is-oriented
motion.spindle-locked
motion.spindle-on
motion.spindle-orient
motion.spindle-orient-angle
motion.spindle-orient-fault
motion.spindle-orient-mode
motion.spindle-reverse
motion.spindle-revs
motion.spindle-speed-cmd-rps
motion.spindle-speed-in
motion.spindle-speed-out
motion.spindle-speed-out-abs
motion.spindle-speed-out-rps
motion.spindle-speed-out-rps-abs

Comp.0.in0
Comp.0.in1
Comp.0.out

or2.0.in0
or2.0.in1
or2.0.out
or2.0.time

and2.0.in0
and2.0.in1
and2.0.out

Or2.1.in0
Or2.1.in1
Or2.1.inout

Spindle enable/clockwise

not.0.in
not.0.out
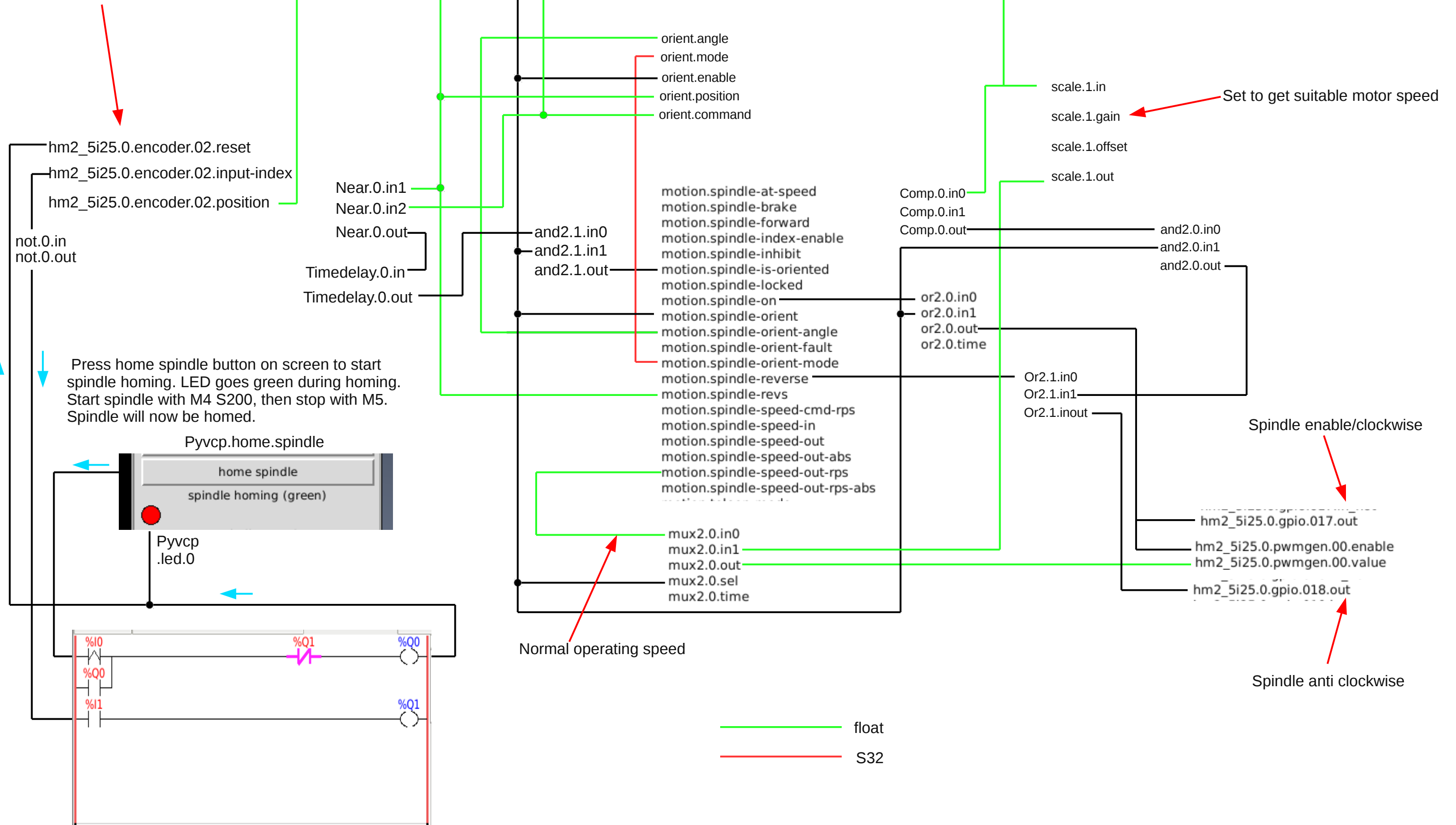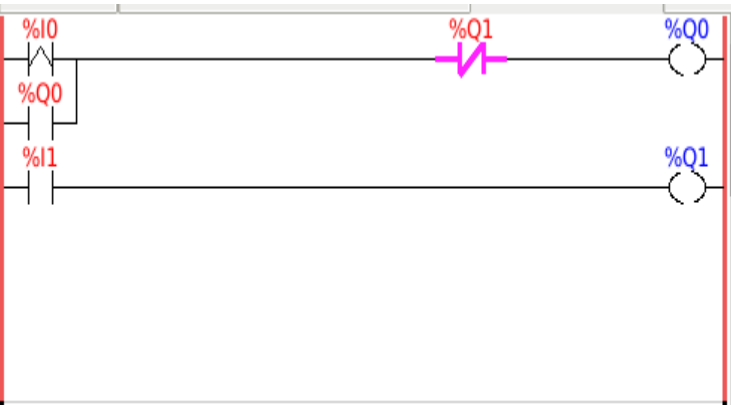
Press home spindle button on screen to start
spindle homing. LED goes green during homing.
Start spindle with M4 S200, then stop with M5.
Spindle will now be homed.

Pyvcp.home.spindle

home spindle

spindle homing (green)

Pyvcp
.led.0

mux2.0.in0
mux2.0.in1
mux2.0.out
mux2.0.sel
mux2.0.time

Normal operating speed

hm2_5i25.0.gpio.017.out
hm2_5i25.0.pwmgen.00.enable
hm2_5i25.0.pwmgen.00.value
hm2_5i25.0.gpio.018.out

Spindle anti clockwise

%I0        %Q1        %Q0
%Q0
%I1                   %Q1

float

S32