

# Gemini GV6 Commands

In addition to the Gemini GV drive configuration commands, the Gemini GV6 will include the following motion control commands:

Motion		Program Flow		Program/Profile Definition		Servo/Tuning	
A	Acceleration	C	Continue	DEF PROG	Define a Program	SGAF	Acceleration Feed-Forward Gain
AA	Average Acceleration	COMEXC	Continue Command Processing Mode	DEF PROF	Define a Profile	SGENB	Enable a Servo Gain Set
AD	Deceleration	COMEXL	Continue Execution on Limit	DEL PROG	Delete a Program	SGSET	Save Current Servo Gains to a Gain Set
ADA	Average Deceleration	COMEXR	Continue Motion on Pause/Continue	DEL PROF	Delete a Profile	SGVF	Velocity Feed-Forward Gain
CMDDIR	Commanded Direction Polarity	COMEXS	Continue Execution on Stop	END	End of Program or Profile	STRGTD	Target Distance Zone
D	Distance	ELSE	Else Condition for IF Statement	ERRORP	Assign Error-handling Program	STRGTE	Target Zone Settling Mode Enable
GO	Initiate Motion	ERROR	Error Checking Enable	PRUN PROF	Run a Profile	STRGTT	Target Settling Timeout Period
K	Kill Motion	GOSUB	Branch to Subroutine	RUN PROG	Run a Program	STRGTV	Target Velocity Zone
PSET	Establish Absolute Position Reference	GOWHEN(T)	Go Statement Based on a Time Delay	STARTP	Assign Startup Program		
S	Stop Motion						
V	Velocity						
VF	Final Velocity						
Homing/Limit		IF(AS)	If Conditional based on Axis Status	Registration			
HOM	Go Home	IF(ASX)	If Conditional based on Extended Axis Status	RE	Registration Enable	Display/Transfer	
HOMA	Home Acceleration	IF(ER)	If Conditional based on Error Status	REG	Registration Distance	TACC	Display Commanded Acceleration Set Point
HOMBAC	Home BackUp Enable	IF(IN)	If Conditional based on Input Status	REGLOD	Registration Lock-Out Distance	TACCA	Display Actual Accel. from Feedback Device
HOMDF	Home Final Direction	IF(SS)	If Conditional based on System Status			TERRLG	Display Error Log
HOMEDG	Home Reference Edge	JUMP	Jump to Program, No Return	Compiled Motion		TGAIN	Display Active Gains
HOMV	Home Velocity	L	Loop	A	Acceleration	TMEM	Display Memory Usage
HOMVF	Home Final Velocity	LN	End of Loop	AD	Deceleration	TPROG	Display Contents of Program
HOMZ	Home to Encoder Z-Channel	MA	Mode Absolute	D	Distance	TSGSET	Display Servo Gain Set
LS	Software Limit Enable	MC	Mode Continuous	DEF PROF	Define Profile	TSTLT	Display Settling Time of Last Move
LSAD	Software Limit Deceleration	NIF	End of IF Statement	DEL PROF	Delete Profile		
LSADA	Software Limit Average Deceleration	PRUN PROF	Run a Compiled Profile	END	End Definition of Program/Profile		
LHAD	Hardware Limit End-of-Travel Deceleration	PS	Pause Program Execution	GOBUF	Store a Motion Segment in Compiled Memory		
LHADA	Hardware Limit End-of Travel Average Deceleration	RUN PROG	Run a Stored Program	GOWHEN(T)	Go Statement Based on a Time Delay		
LSNEG	Software EOT Limit - Negative Travel Range	T	Time Delay	MC	Mode Continuous		
LSPOS	Software EOT Limit - Positive Travel Range	TRACE	Program Trace Mode Enable	POUTA	Output State, Compiled		
		TRGFN	Trigger Functions	PRUN PROF	Run a Compiled Profile		
		TRGLOT	Trigger Interrupt Lockout Time	SGENB	Enable a Servo Gain Set		
		WAIT(AS)	Wait for Axis Status	V	Velocity		
		WAIT(ASX)	Wait for Extended Axis Status	VF	Final Velocity		
		WAIT(IN)	Wait for Input Status				
		XONOFF	Enable or Disable XON/XOFF				
				Inputs/Outputs			
				INFNC	Input Function Assignment		
				INSELP	Program Selection with Inputs, Enable		
				OUT	Set Output State		
				OUTFNC	Output Function Assignment		

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