

Unexpected realtime delay on task 0 with period 1000000
This Message will only display once per session.

1 = 5 μ s.

Axis Scale Calculation

Step Motor Scale

| | | | | | | | | |
|--|--------|---|---|---|----|---|---|----------|
| <input type="checkbox"/> Pulley teeth (motor:Leadscrew): | 1 | - | + | : | 10 | - | + | |
| <input type="checkbox"/> Worm turn ratio (Input:Output) | 1 | - | + | : | 1 | - | + | |
| <input type="checkbox"/> Microstep Multiplication Factor: | 5 | | | | | | | |
| <input checked="" type="checkbox"/> Leadscrew Metric Pitch | 5.0000 | | | | | - | + | mm / rev |
| <input type="checkbox"/> Leadscrew TPI | 5.0000 | | | | | - | + | TPI |
| Motor steps per revolution: | 1000 | | | | | - | + | |

Encoder Scale

| | | | | | | | | |
|--|--------|---|---|---|---|---|---|------------------|
| <input type="checkbox"/> Pulley teeth (encoder:Leadscrew): | 1 | - | + | : | 1 | - | + | |
| <input type="checkbox"/> Worm turn ratio (Input:Output) | 1 | - | + | : | 1 | - | + | |
| <input type="checkbox"/> Leadscrew Metric Pitch | 5.0000 | | | | | - | + | mm / rev |
| <input type="checkbox"/> Leadscrew TPI | 5.0000 | | | | | - | + | TPI |
| Encoder lines per revolution: | 1000 | | | | | - | + | X 4 = Pulses/Rev |

Calculated Scale

| | |
|--------------------------|-----------|
| motor steps per unit: | 2000.0000 |
| encoder pulses per unit: | |

Motion Data

| | |
|----------------------------------|---------------------|
| Calculated Axis SCALE: | 2000.0 Steps / mm |
| Resolution: | 0.0005000 mm / Step |
| Time to accelerate to max speed: | 0.0444 sec |
| Distance to acheave max speed: | 0.7407 mm |
| Pulse rate at max speed: | 66.7 Khz |
| Motor RPM at max speed: | 4000 RPM |

Cancel

Apply

direction change), the increased dirhold value has no effect.
make each step, and we have the same 31,250 step per second.
The 11 μ s latency number used in this example is very good. If
larger latency, like 20 or 25 μ s, the top step rate for both the
formulas apply for calculating the optimum BAS