

```
# Generated by PNCconf at Wed Oct 3 14:53:45 2018
# Änderungen an dieser Datei werden beim nächsten
# overwritten when you run PNCconf again
```

```
loadrt [KINS]KINEMATICS
loadrt [EMCMOT]EMCMOT servo_period_nsec=[EMCMOT]SERVO_PERIOD num_joints=
[KINS]JOINTS
loadrt hostmot2
loadrt hm2_pci config=" num_encoders=6 num_pwmgens=0 num_stepgens=0 sserial_port_0
=000xxx"
setp hm2_5i25.0.watchdog.timeout_ns 5000000
loadrt pid names=pid.x,pid.y,pid.z,pid.s
```

```
addf hm2_5i25.0.read servo-thread
addf motion-command-handler servo-thread
addf motion-controller servo-thread
addf pid.x.do-pid-calcs servo-thread
addf pid.y.do-pid-calcs servo-thread
addf pid.z.do-pid-calcs servo-thread
addf pid.s.do-pid-calcs servo-thread
addf hm2_5i25.0.write servo-thread
```

```
# ---estop signals---
```

```
loadrt and2 count=1
addf and2.0 servo-thread
```

```
net estop1 and2.0.in0 <= iocontrol.0.user-enable-out
net estop2 and2.0.in1 <= hm2_5i25.0.7i77.0.0.input-00
```

```
net estop-out and2.0.out => iocontrol.0.emc-enable-in
```

```
#---Limit/Null/home-x---
```

```
loadrt or2 count=6
```

```
addf or2.0 servo-thread
addf or2.1 servo-thread
addf or2.2 servo-thread
addf or2.3 servo-thread
addf or2.4 servo-thread
addf or2.5 servo-thread
```

```
net x-lim- or2.0.in0 <= hm2_5i25.0.7i77.0.0.input-01-not
net x-null- or2.0.in1 <= hm2_5i25.0.7i77.0.0.input-03-not
net x-neg-lim/null or2.0.out => joint.0.neg-lim-sw-in joint.0.home-sw-in
```

```
net x-lim+ or2.1.in0 <= hm2_5i25.0.7i77.0.0.input-02-not
net x-null+ or2.1.in1 <= hm2_5i25.0.7i77.0.0.input-04-not
net x-pos-lim/null or2.1.out => joint.0.pos-lim-sw-in
```

```
#---Limit/Null-y---
```

```
net y-lim- or2.2.in0 <= hm2_5i25.0.7i77.0.0.input-05-not
net y-null- or2.2.in1 <= hm2_5i25.0.7i77.0.0.input-07-not
net y-neg-lim/null or2.2.out => joint.1.neg-lim-sw-in joint.1.home-sw-in
```

```
net y-lim+ or2.3.in0 <= hm2_5i25.0.7i77.0.0.input-06-not
```