

POSTGUI\_HALFILE = postgui\_call\_list.hal  
SHUTDOWN = shutdown.hal

[HALUI]

[KINS]  
JOINTS = 3  
KINEMATICS = trivkins coordinates=XYZ

[TRAJ]  
COORDINATES = XYZ  
LINEAR\_UNITS = mm  
ANGULAR\_UNITS = degree  
DEFAULT\_LINEAR\_VELOCITY = 2.50  
MAX\_LINEAR\_VELOCITY = 25.00

[EMCIO]  
EMCIO = io  
CYCLE\_TIME = 0.100  
TOOL\_TABLE = tool.tbl

#\*\*\*\*\*

[AXIS\_X]  
MAX\_VELOCITY = 83.33333  
MAX\_ACCELERATION = 250.0  
MIN\_LIMIT = -0.01  
MAX\_LIMIT = 1400.0

[JOINT\_0]  
TYPE = LINEAR  
HOME = 100.0  
ERROR = 1.0  
MIN\_ERROR = 0.5  
MAX\_VELOCITY = 83.33333  
MAX\_ACCELERATION = 250.0  
P = 10  
I = 0  
D = 0  
FF0 = 0  
FF1 = 0.023  
FF2 = 0  
BIAS = 0  
DEADBAND = 0  
MAX\_OUTPUT = 0  
ENCODER\_SCALE = 409.6  
OUTPUT\_SCALE = 10  
OUTPUT\_MIN\_LIMIT = -10  
OUTPUT\_MAX\_LIMIT = 10  
MIN\_LIMIT = -0.01  
MAX\_LIMIT = 1400.0

HOME\_OFFSET = 0.0  
HOME\_SEARCH\_VEL = -10.0  
HOME\_LATCH\_VEL = -4.0  
HOME\_FINAL\_VEL = 40.0  
HOME\_SEQUENCE = 2  
HOME\_USE\_INDEX = NO  
HOME\_IGNORE\_LIMITS = YES