

ControlDesk NG Project: het\_trk Experiment: TrackerController - [Initialize] Platform / trackercontroller2.sdf(#5) /

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Platform

1 Tracker Monitor 2 TrackerOperation 3 Initialize 4 MOVA\_RTF 5 Tracker State 6 TMCS\_interface 7 Sensors HETDEX 8 Digital In 9 Fault Monitoring

Vel FF Mode Y Track  
 Filtered Derivat  
 Unfiltered Deriv  
 2nd Order Deriv

Note: Upper and Lower X Track and Slew Open Loop Limits Can be set from CDNG. See Y for example.

### Encoder Incremental Temporary Cal Settings

UX Abs Linear Sensor	UX - Position (m)	UX - Offset Init (m)	UX HH Zero	X Ramp Acc Lim	H1 Acc (m/s <sup>2</sup> )	H4 Acc (m/s <sup>2</sup> )
-0.250782	-0.251160	0.199438	Zero	+0.002	+0.002	+0.002
LX Abs Linear Sensor	LX - Position (m)	LX - Offset Init (m)	LX HH Zero	X Ramp Acc Lim	H2 Acc (m/s <sup>2</sup> )	H5 Acc (m/s <sup>2</sup> )
-0.256866	-0.251091	0.166997	Zero	+0.002	+0.002	+0.002
Y Abs Linear Sensor	Y - Position (m)	Y - Offset Init (m)	Y HH Zero	Ramp Acc Lim	H3 Acc (m/s <sup>2</sup> )	H6 Acc (m/s <sup>2</sup> )
0.952581	0.935842	-0.288974	Zero	+0.002	+0.002	+0.002
Rho HH ABS Position	Rho - Siko Position (rad)	Rho - Offset Init (rad)	Rho Siko Zero	Init Offset Enable		
-0.093532	-0.092323	-0.000105	Zero	<input checked="" type="radio"/> Disable <input type="radio"/> Enable		

Y Input Channel  
 Input 2  
 Input 5  
 Input 6

GlobalLimiterOnOff  
0.000

Command Limiter  
 Disable  
 Enable

UX - Delta abs (m)	UX - DR1 (m)	UX - Error	Init Time Left (s)	Init End Flag
-0.194	1.881	0.000	0.000	0.000
LX - Delta abst Init (m)	LX - DR1 Init (m)	LX - Error		
0.107	0.111	0.000		

Platform/Device Log Variables Measurement Data Pool

Recording (Cycle 1250 of 7200) 576.9 s R: 23.1 125920 R: 0.0 s