

the speed is a REAL value for units/second. You can change this parameter while the motor is running.

#### Note

The Axis of Motion may not react to small changes in the Speed parameter, especially if the configured acceleration or deceleration time is short and the difference between the configured maximum speed and start/stop speed is large.

The Dir parameter determines the direction to move when RUN is enabled. You cannot change this value when the RUN parameter is enabled.

The Error parameter (Page 794) contains the result of this subroutine.

The C\_Pos parameter contains the current position of the Axis of Motion. Based upon the units of measurement selected, the value is either a number of pulses (DINT) or the number of engineering units (REAL).

The C\_Speed parameter contains the current speed of the Axis of Motion. Based upon the units of measurement selected, the value is either the number of pulses/second (DINT) or the engineering units/second (REAL).

The C\_Dir parameter indicates the current direction of the motor:

- Signal state of 0 = positive
- Signal state of 1 = negative

### 14.4.3.4 AXISx\_GOTO subroutine

Table 14-10 AXISx\_GOTO

LAD / FBD	STL	Description
	<b>CALL AXISx_GOTO,</b> <b>START, Pos, Speed,</b> <b>Mode, Abort, Done,</b> <b>Error, C_Pos, C_Speed</b>	The AXISx_GOTO subroutine commands the Axis of Motion to go to a desired location.

Table 14-11 Parameters for the AXISx\_GOTO subroutine

Inputs/Outputs	Data type	Operands
START	BOOL	I, Q, V, M, SM, S, T, C, L, Power Flow
Pos, Speed	DINT, REAL	ID, QD, VD, MD, SMD, SD, LD, AC, *VD, *AC, *LD, Constant
Mode	BYTE	IB, QB, VB, MB, SMB, SB, LB, AC, *VD, *AC, *LD, Constant
Abort, Done	BOOL	I, Q, V, M, SM, S, T, C, L