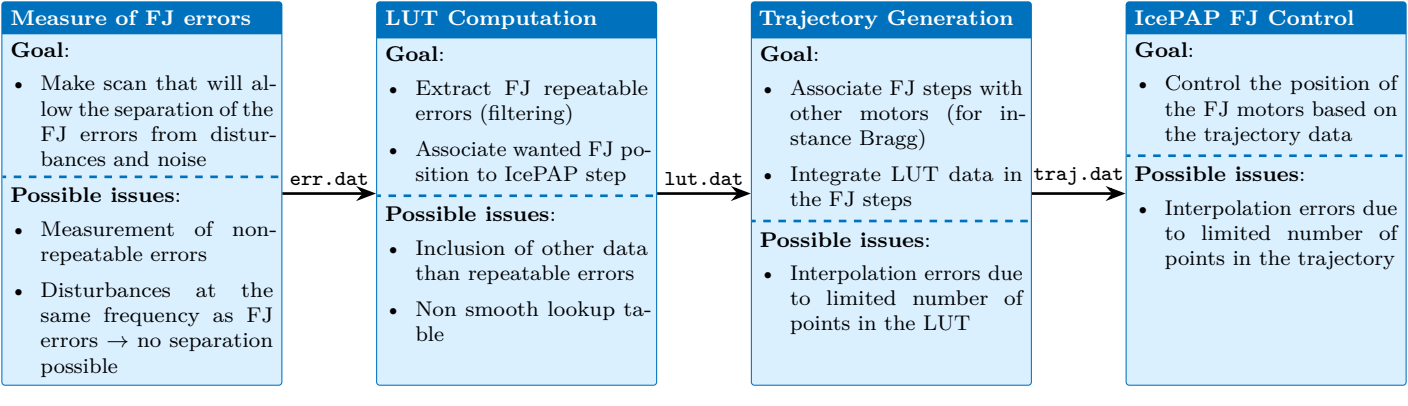
Measure of FJ errors
Goal:
• Make scan that will allow the separation of the FJ errors from disturbances and noise
Possible issues:
• Measurement of non-repeatable errors
• Disturbances at the same frequency as FJ errors → no separation possible
err.dat
LUT Computation
Goal:
• Extract FJ repeatable errors (filtering)
• Associate wanted FJ position to IcePAP step
Possible issues:
• Inclusion of other data than repeatable errors
• Non smooth lookup table
lut.dat
Trajectory Generation
Goal:
• Associate FJ steps with other motors (for instance Bragg)
• Integrate LUT data in the FJ steps
Possible issues:
• Interpolation errors due to limited number of points in the LUT
traj.dat
IcePAP FJ Control
Goal:
• Control the position of the FJ motors based on the trajectory data
Possible issues:
• Interpolation errors due to limited number of points in the trajectory