Programming Language TMscript

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Contents

1. OVERVIEW 12

2. EXPRESSION 13

2.1 Types 13
2.2 Variables and Constants 14
2.3 Array 18
2.4 Operator Symbols 19
2.5 Data Type Conversion 22
2.6 Endianness and Conversion 25
2.7 Warning 27

3. SCRIPT PROJECT PROGRAMMING 29

3.1 define 29
3.2 main 29
3.3 closestop 30
3.4 errorstop 31
3.5 Customized Function 32
3.6 Comment 33
3.7 Variable 34
3.8 Multi-Line Input 37
3.9 Conditional Statements 38
3.9.1 if 38
3.9.2 switch 39
3.10 Loop Statements 42
3.10.1 for 42
3.10.2 while 43
3.10.3 do while 44
3.11 Branching Statements 45
3.11.1 break 45
3.11.2 continue 46
3.11.3 return 46
3.12 Thread 47
3.12.1 ThreadRun() 47
3.12.2 ThreadID() 48
3.12.3 ThreadState() 49
3.12.4 ThreadExit() 49

4. GENERAL FUNCTIONS 52

4.1 Byte_ToInt16() 52
4.2 Byte_ToInt32() 54
4.3 Byte_ToFloat() 55
4.4 Byte_ToDouble() 56
4.5 Byte_ToInt16Array() 57
4.6 Byte_ToInt32Array() 59

TECHMAN ROBOT INC.
5F., No. 58-2, Huaya 2nd Rd., Guishan Dist., Taoyuan City, 333411 , Taiwan

4.7 Byte_ToFloatArray() 60
4.8 Byte_ToDoubleArray() 61
4.9 Byte_ToString() 62
4.10 Byte_Concat() 63
4.11 String_ToInteger() 66
4.12 String_ToFloat() 68
4.13 String_ToDouble() 70
4.14 String_ToByte() 72
4.15 String_IndexOf() 73
4.16 String_LastIndexOf() 75
4.17 String_DiffIndexOf() 77
4.18 String_Substring() 78
4.19 String_Split() 81
4.20 String_Replace() 82
4.21 String_Trim() 83
4.22 String_ToLower() 85
4.23 String_ToUpper() 86
4.24 Array_Append() 87
4.25 Array_Insert() 88
4.26 Array_Remove() 89
4.27 Array_Equals() 90
4.28 Array_IndexOf() 92
4.29 Array_LastIndexOf() 94
4.30 Array_Reverse() 96
4.31 Array_Sort() 98
4.32 Array_SubElements() 99
4.33 ValueReverse() 101
4.34 GetBytes() 105
4.35 GetString() 109
4.36 GetToken() 116
4.37 GetAllTokens() 124
4.38 GetNow() 126
4.39 GetNowStamp() 128
4.40 GetVarValue() 131
4.41 SetVarValue() 132
4.42 Length() 133
4.43 Ctrl() 135
4.44 XOR8() 137
4.45 SUM8() 139
4.46 SUM16() 141
4.47 SUM32() 143
4.48 CRC16() 145
4.49 CRC32() 147
4.50 ListenPacket() 149
4.51 ListenSend() 150
4.52 VarSync() 152

5. GENERAL FUNCTIONS (SCRIPT) 154

5.1 Exit() 154
5.2 Pause() 156
5.3 Resume() 157
5.4 WaitFor() 158
5.5 Sleep() 159
5.6 Display() 160
5.7 ExecText() 162
5.8 ExecFile() 163
5.9 RedirectToProject() 164

6. MATH FUNCTIONS 165

6.1 abs() 165
6.2 pow() 166
6.3 sqrt() 168
6.4 ceil() 169
6.5 floor() 170
6.6 round() 171
6.7 random() 173
6.8 sum() 175
6.9 average() 176
6.10 stdevp() 177
6.11 stdevs() 178
6.12 min() 179
6.13 max() 180
6.14 d2r() 181
6.15 r2d() 182
6.16 sin() 183
6.17 cos() 184
6.18 tan() 185
6.19 asin() 186
6.20 acos() 187
6.21 atan() 188
6.22 atan2() 189
6.23 log() 190
6.24 log10() 192
6.25 norm2() 193
6.26 dist() 194
6.27 trans() 195
6.28 inversetrans() 197
6.29 applytrans() 198
6.30 interpoint() 200
6.31 changeref() 201
6.32 points2coord() 203
6.33 intercoord() 205
6.34 coorshift() 206
6.35 inversekin() 207
6.36 forwardkin() 209

6.37 joint2pose() 210

7. FILE FUNCTIONS 211

7.1 File_ReadBytes() 212
7.2 File_ReadText() 213
7.3 File_ReadLines() 214
7.4 File_NextLine() 216
7.5 File_NextEOF() 219
7.6 File_WriteBytes() 220
7.7 File_WriteText() 224
7.8 File_WriteLine() 227
7.9 File_WriteLines() 230
7.10 File_Exists() 233
7.11 File_Length() 234
7.12 File_Delete() 235
7.13 File_Copy() 236
7.14 File_CopyImage() 237
7.15 File_GetImage() 239
7.16 File_Replace() 241
7.17 File_GetToken() 242
7.18 File_GetAllTokens() 246
7.19 File_GetFiles() 248
7.20 File_LogWrite() 250

8. SERIAL PORT FUNCTIONS 252

8.1 SerialPort Class 252
8.2 com_open() 253
8.3 com_close() 254
8.4 com_read() 255
8.5 com_read_string() 261
8.6 com_write() 266
8.7 com_writeline() 268

9. SOCKET FUNCTIONS 270

9.1 Socket Class 270
9.2 socket_open() 271
9.3 socket_close() 272
9.4 socket_read() 273
9.5 socket_read_string() 279
9.6 socket_send() 284
9.7 socket_sendline() 286

10. MANUAL DECISION FUNCTIONS 289

10.1 MDecision Class 289
10.1.1 Reset() 290

10.1.2 Title() 290
10.1.3 Description() 290
10.1.4 Timeout() 290
10.1.5 TimeoutDefaultCase() 291
10.1.6 Case() 291
10.1.7 Show() 293

11. PARAMETERIZED OBJECTS 295

11.1 Point 296
11.2 Base 297
11.3 TCP 298
11.4 VPoint 300
11.5 IO 301
11.6 Robot 304
11.7 FT 306
11.8 Env 308

12. ROBOT TEACH CLASS 309

12.1 TPoint Class 309
12.2 TBase Class 313
12.2.1 GetValue() 314
12.2.2 SetValue() 314
12.2.3 ConvShift() 315
12.3 TTCP Class 317

13. ROBOT MOTION & VISION JOB FUNCTION 320

13.1 QueueTag() 320
13.2 WaitQueueTag() 321
13.3 CheckQueueTag() 322
13.4 StopAndClearBuffer() 324
13.5 ChangeBase() 325
13.6 ChangeTCP() 327
13.7 ChangeLoad() 330
13.8 PTP() 331
13.9 Move_PTP() 336
13.10 Line() 337
13.11 Move_Line() 340
13.12 Circle() 343
13.13 PLine() 346
13.14 Move_PLine() 347
13.15 LineSingularity() 348
13.16 CollisionCheck() 349
13.17 PVTEnter() 351
13.18 PVTExit() 352
13.19 PVTPoint() 353
13.20 PVTPause() 355

13.21 PVTResume() 356
13.22 PathOffset_Set() 357
13.23 PathOffset_Get() 360
13.24 PathOffset_IsEnabled() 361
13.25 PathOffset_AlphaFilter() 362
13.26 PathOffset_MaxOffset() 363
13.27 Velocity() 366
13.28 Position() 370
13.29 SetTCPSpeedLimit() 374
13.30 SetAccTable() 376
13.31 GetAccTable() 379
13.32 Vision_DoJob() 380
13.33 Vision_DoJob_PTP() 381
13.34 Vision_DoJob_Line() 382

14. VISION FUNCTIONS 384

14.1 Vision_IsJobAvailable() 384
14.2 Multi-Object Result Output and Flying Trigger/Inspection Tasks 385
14.2.1 Vision_GetOutputArraySize() 385
14.2.2 Vision_GetOutputArrayValue() 387
14.3 Vision_GetTriggerJobOutputCount() 395
14.4 Vision_GetTriggerJobOutputValue() 396

15. EXTERNAL SCRIPT 398

15.1 Listen Node 398
15.2 Communication Protocol 399
15.3 TMSCT 401
15.4 TMSTA 403
15.5 CPERR 406
15.6 ScriptListen() 408
15.7 ScriptExit() 410
15.8 Priority Commands 411

16. MODBUS FUNCTIONS 414

16.1 ModbusTCP Class 414
16.1.1 Preset() 414
16.1.2 IODDPreset() 416
16.2 ModbusRTU Class 417
16.2.1 Preset() 417
16.2.2 IODDPreset() 419
16.3 modbus_open() 421
16.4 modbus_close() 422
16.5 modbus_read() 423
16.6 modbus_read_int16() 426
16.7 modbus_read_int32() 428
16.8 modbus_read_float() 430

16.9 modbus_read_double()..... 432
16.10 modbus_read_string()..... 434
16.11 modbus_write()..... 436

17. TM ETHERNET SLAVE 440

17.1 GUI Setting..... 440
17.2 Data Table..... 441
17.3 Communication Protocol..... 443
17.4 TMSVR..... 445
17.4.1 Mode = 0 (the status the server responds to the client command processing).....446
17.4.2 Mode = 1 BINARY.....448
17.4.3 Mode = 2 STRING.....450
17.4.4 Mode = 3 JSON 451
17.4.5 Mode = 11 BINARY (Request read) 452
17.4.6 Mode = 12 STRING (Request read) 454
17.4.7 Mode = 13 JSON (Request read) 455
17.5 svr_read()..... 456
17.6 svr_write()..... 457

18. PROFINET FUNCTIONS.....458

18.1 profinet_read_input()..... 459
18.2 profinet_read_input_int()..... 463
18.3 profinet_read_input_float()..... 465
18.4 profinet_read_input_string()..... 467
18.5 profinet_read_input_bit()..... 468
18.6 profinet_read_output()..... 470
18.7 profinet_read_output_int()..... 474
18.8 profinet_read_output_float()..... 476
18.9 profinet_read_output_string()..... 478
18.10 profinet_read_output_bit()..... 479
18.11 profinet_write_output()..... 481
18.12 profinet_write_output_bit()..... 488

19. ETHERNET/IP FUNCTIONS 493

19.1 eip_read_input()..... 494
19.2 eip_read_input_int()..... 497
19.3 eip_read_input_float()..... 499
19.4 eip_read_input_string()..... 501
19.5 eip_read_input_bit()..... 502
19.6 eip_read_output()..... 504
19.7 eip_read_output_int()..... 508
19.8 eip_read_output_float()..... 510
19.9 eip_read_output_string()..... 512
19.10 eip_read_output_bit()..... 513
19.11 eip_write_output()..... 515
19.12 eip_write_output_bit()..... 522

20. ETHERCAT FUNCTIONS 527

20.1 ethercat_read_input() 528
20.2 ethercat_read_input_int() 531
20.3 ethercat_read_input_float() 533
20.4 ethercat_read_input_string() 535
20.5 ethercat_read_input_bit() 536
20.6 ethercat_read_output() 538
20.7 ethercat_read_output_int() 542
20.8 ethercat_read_output_float() 544
20.9 ethercat_read_output_string() 546
20.10 ethercat_read_output_bit() 547
20.11 ethercat_write_output() 549
20.12 ethercat_write_output_bit() 555

21. CC-LINK FUNCTIONS 561

21.1 cclink_read_input() 562
21.2 cclink_read_input_int16() 565
21.3 cclink_read_input_int() 567
21.4 cclink_read_input_float() 569
21.5 cclink_read_input_string() 571
21.6 cclink_read_input_bit() 572
21.7 cclink_read_output() 575
21.8 cclink_read_output_int16() 579
21.9 cclink_read_output_int() 581
21.10 cclink_read_output_float() 583
21.11 cclink_read_output_string() 585
21.12 cclink_read_output_bit() 586
21.13 cclink_write_output() 589
21.14 cclink_write_output_bit() 595

22. REAL-TIME REMOTE SERVER 601

22.1 GUI Setting 601
22.2 Communication Protocol 602
22.3 TMRTS 604
22.3.1 Mode = 0 (the server status response to the client command processing) 606
22.3.2 Mode = 1 BINARY 611
22.3.3 Mode = 7 START/STOP Data Streaming 613
22.3.4 Mode = 8 SET Streaming Frequency 614
22.3.5 Mode = 9 SET Streaming Data 615
22.4 TMRTC 616
22.4.1 Mode = 0 (the server status response to the client command processing) 618
22.4.2 Mode = 1 BINARY 622
22.4.3 Mode = 7 START/STOP Motion Control 623
22.4.4 Mode = 8 SET Motion Control Settings 624

23. COMPLIANCE FUNCTIONS 626

23.1 Compliance Class 626
23.1.1 Reset() 626
23.1.2 Frame() 626
23.1.3 HighResistance() 627
23.1.4 Single() 627
23.1.5 Teach() 627
23.1.6 Multiple() 628
23.1.7 Impedance() 629
23.1.8 Timeout() 629
23.1.9 DInput() 630
23.1.10 AInput() 631
23.1.11 Condition() 631
23.1.12 Start() 632
23.1.13 Stop() 632

24. TOUCHSTOP FUNCTIONS 635

24.1 TouchStop class 635
24.1.1 Reset() 636
24.1.2 Frame() 636
24.1.3 HighResistance() 636
24.1.4 BrakeDistance() 637
24.1.5 RecordPosPoint() 637
24.1.6 Single() 638
24.1.7 Teach() 639
24.1.8 AdvSet() 640
24.1.9 Timeout() 641
24.1.10 DInput() 641
24.1.11 AInput() 642
24.1.12 Condition() 643
24.1.13 Resisted() 644
24.1.14 FTReached() 644
24.1.15 Start() 645
24.1.16 Stop() 646
24.1.17 GetStoppedPos() 646
24.1.18 GetTriggeredPos() 647
24.1.19 GetMovingDistance() 647

25. FORCE CONTROL FUNCTIONS 652

25.1 FTSensor Class 652
25.1.1 Open() 654
25.1.2 Close() 654
25.2 Force Class 654
25.2.1 Reset() 655
25.2.2 Frame() 655
25.2.3 Distance() 657
25.2.4 ProtectionSpeed() 657
25.2.5 FTSet() 657

25.2.6 Trajectory()....659
25.2.7 Timeout()....660
25.2.8 AllowPosTol()....661
25.2.9 DInput()....661
25.2.10 AInput()....662
25.2.11 FTReached()....663
25.2.12 Condition()....664
25.2.13 Start()....664
25.2.14 Stop()....665

REVISION HISTORY TABLE....670

1. Overview

TMscript is the programming language of Techman Robot applicable to Flow projects and Script projects. Refer to the table below for the main scope of applications.

- Scope of Applications

Application	Flow Projects			Script Projects
	Set Node (& other nodes)	Listen Node (external scripts)	Script Node	
Expression	✓	✓	✓	✓
define/main/closestop/errorstop				✓
Customized Function				✓
Comment		✓	✓	✓
Global variables in the Project	✓	✓	✓	✓
Local variables in the Function		✓	✓	✓
Multiline Input		✓	✓	✓
Conditional Statement		✓	✓	✓
Loop Statement		✓	✓	✓
Branching Statement		✓	✓	✓
Thread Function				✓
General Function	✓	✓	✓	✓
General Function (Script)		✓	✓	✓
Math Function	✓	✓	✓	✓
File Function	✓	✓	✓	✓
Serial Port Class		✓	✓	✓
Serial Port Function	✓	✓	✓	✓
Socket Class				
Socket Function	✓	✓	✓	✓
MDecision Class		✓	✓	✓
Parameterized Object	✓	✓	✓	✓
Robot Teach Class		✓	✓	✓
Robot Motion & Vision Job Function		✓	✓	✓
Vision Function	✓	✓	✓	✓
ScriptListen Function		✓	✓	✓
External Script/Priority Command		✓		
Modbus TCP/RTU Class		✓	✓	✓
Modbus Function	✓	✓	✓	✓
TM Ethernet Slave Function	✓	✓	✓	✓
Profinet Function	✓	✓	✓	✓
EtherNet/IP Function	✓	✓	✓	✓
EtherCAT Function	✓	✓	✓	✓
CC-Link Function	✓	✓	✓	✓
Real-Time Remote Server Function				
Compliance Class		✓	✓	✓
TouchStop Class		✓	✓	✓
FTSensor Class		✓	✓	✓
Force Class		✓	✓	✓

2. Expression
2.1 Types

Different data types of variables can be declared in Variable Manager.

byte	8bit integer	unsigned	0 to 255	significant digit 3
int	32bit integer	signed	-2147483648 to 2147483647	significant digit 10
float	32bit floating-point	signed	-3.4028235E+38 to 3.4028235E+38	significant digit 7
double	64bit floating-point	signed	-1.7976931348623157E+308 to 1.7976931348623157E+308	significant digit 15
bool	Boolean		true or false	
string	string			

In function terms, the integer type further goes by int16 and int32. The default is int32.

int16	16bit integer	signed	-32768 to 32767	significant digit 5
int32	32bit integer	signed	-2147483648 to 2147483647	significant digit 10

2.2 Variables and Constants

1. Variables

Users can only use numeric or English character combinations without special characters or other characters, and the name after the combination cannot be a numeric value, a string, or a Boolean value.

Numbers	0123456789
Characters	a-z, A-Z, _

Example

```
Int i = 0
string s = "ABC"
string s1 = "DEF"
string s2 = "123"
```

Without double quotation marks, strings will be taken as variables.

```
s = s1 + " and " + s2    // s = "DEF and 123"
                         // s, s1, s2 are variable, and " and " is a string.
```

In addition to variables, the naming rule also applies to constants, numbers, strings, and Booleans except that string constants need to be enclosed in double quotes.

When a variable is generated in TMflow, a prefix is added based on the source. To use the variable for writing or reading, users must enter the full name including the prefix word such as var_s1 or g_s2. For the rules of adding prefixes, refer to the respective description in variable setting pages.

2. Numbers

- Decimal integer, decimal floating-point, binary, hexadecimal integer and scientific notation are supported.

Decimal integer	123
	-123
	+456
Decimal float	34.567
	-8.9
Binary	0b0000111
	0B1110000
Hexadecimal integer	0x123abc
	0X00456DEF
Scientific notation	3.4e5
	2.3E-4

- For binary and hexadecimal notation, there is no floating-point.
- The notation of number is not case sensitive.
  For example:
  0b0011 equals 0B0011
  0xabcD equals 0XABCD, 0xABCd, 0Xabcd etc.
  3.4e5 equals 3.4E5
- The system determines the data types of numbers automatically when using numbers as constants. The rule is to conclude bit types from the smaller to the greater such as

```
100          // data type: byte          // 100 is in the value range of data type: byte.
1000         // data type: int
1.11         // data type: float     //1.11 is in the value range of data type: float.
```

To assign the data type, use variable declaration or conversion to do so such as

```
byte b = 100 // variable b = 100 as data type: byte
int i = 100      // variable i = 100 as data type: int
(int)100         // constant 100 as data type: int
(float)100       // constant 100 as data type: float
```

For function calls, the system determines the data types of arguments and selects the respective syntax. If there is no respective syntax, the system determines the compatible syntax with the rule concluding bit types from the smaller to the greater such as

```
GetBytes(100, 0, 0)          // {0x64,0x00,0x00,0x00} // 100 and the 0s come with the data type: byte, but the syntax goes with GetBytes(int, int, int). The system, therefore, converts 100 and the 0s into the data type: int to proceed with the call syntax.
GetBytes(100)      // {0x64} // 100 comes with the data type: byte. in the syntax GetBytes(?) to go with any data types. Therefore, the system takes 100 as a constant in data type: byte to proceed the call syntax.
```

- Byte can only present unsigned numbers in 8 bits ranging from 0 to 255. As a result, if a negative sign is assigned to the byte type or through calculation, it will still save the 8-bit unsigned value only.

  For example:

```
byte b = -100        // Error      // -100 mismatches with the value range of byte.
byte b = 0 - 100     // b = 156
                     // 0-100=-100 (0xFFFFFF9C). Saved 8 bits as 0x9C. The value equals 156.
b = 0 - 1            // b = 255  // 0-1=-1 (0xFFFFFFFF) Saved 8 bits as 0xFF The value equals 255.
b = 255 + 1          // b = 0      // 255+1=256 (0x100) Saved 8 bits as 0x00 The value equals 0.
```

- Int can present signed numbers in 32 bits ranging from -2147483648 to 2147483647. If the calculation exceeds the value range, it will still save the 32-bit signed integer value only.

  For example:

```
int i = -2147483648 - 1      // i = 2147483647    // -2147483648 - 1 = -2147483649 (0xFFFFFFFF 7FFFFFFF) Saved 32 bits as 0x7FFFFFFF. The value equals 2147483647.
i = 2147483647 + 1           // i = -2147483648    // 2147483647 + 1 = 2147483648 (0x80000000) Save 32 bits in the method of signed integer value. The value equals -2147483648
```

3. String

When inputting string constant, double quotation marks shall be placed in pairs around the string to avoid the recognition error of variable and string. ◦

For example

```
"Hello World! "
"Hello TM""5"      (If " is one of the character in the string, use two ("") instead of one (").
```

- Control character in double quotation mark are not supported.

  For example:

  "Hello World!\r\n" (the output would be **Hello World!\r\n** string)

- Without double quotation marks, the compiling will follows the rules below

1. Numbers will be viewed as numbers
2. The combination of numbers and characters will be viewed as variable as long as the variable does exist.
3. If the variable does not exist, it will be compiled as string with a warning message.

- The combination of string and variable
  1. Inside double quotation marks, variables will not be combined as variables
     For example:
     ```
     s = "TM5"                  // s = "TM5"
     s1 = "Hi, s Robot"         // s1 = "Hi, s Robot"
     ```
  2. Standard syntax. Double quotation marks need to be placed around the string, and plus sign (+) shall be used to link variables and numbers
     Example:
     ```
     s1 = "Hi, " + s + " Robot"    // s1 = "Hi, TM5 Robot"
     ```
  3. Compatible syntax (not recommended). The single quotation marks can be placed around the variables, but a warning message will be sent out
     For example:
     ```
     single quotation marks    "Hi, 's' Robot"          // s1 = "Hi, TM5 Robot"
     "Hi, 'x' Robot"           // s1 = "Hi, 'x' Robot"  // Because variable x does not exist, 'x' is viewed as string
     ```
  4. Single quotation marks do not support element value retrieval with array indexes. The standard format with double quotation marks should be used.
     For example
     ```
     string[] ss = {"Techman", "Robot"}
     "Hi, 's' 'ss[0]' Robot"  // s1 = "Hi, TM5 'ss[0]' Robot"
                              // 'ss[0]' is invalid
     "Hi, " +  s + " " + ss[0] + " Robot"    // s1 = "Hi, TM5 Techman Robot"
     ```
  5. Single quotation marks cannot be presented by "' If users would like to input '(variable name)', The standard format with double quotation marks should be used.
     For example
     ```
     "Hi, 's' Robot"                 // s1 = "Hi, TM5 Robot"
     // If s1 = "Hi, 's' Robot" is what you want, please use the following syntax.
     "Hi, '" + "s" + "' Robot"  // s1 = "Hi, 's' Robot"
     ```
- For control character, e.g. new line, please use Ctrl() command.
  For example
  ```
  s1 = "Hi, " + Ctrl("\r\n") + s + " Robot"   or   "Hi, " + NewLine + s + " Robot"
  Hi,
  TM5 Robot
  ```
- Reserved characters is similar to variables, no double quotation marks is needed. (But single quotation mark is not supported)
  1. empty — empty string, equals ""
  2. newline or NewLine — new line, equals Ctrl("\r\n") or Ctrl(0x0D0A)

4. Boolean

True or false value of logic.

Denote true value	true True
Denote false value	false

False

The Boolean value is case sensitive. Misuses of capital letters such as TRue will be taken as a variable or a string.

2.3 Array

- Array is a set of data with the same data type. The initial value is assigned with {}, and every element remains the characteristic of its data type.
  For example
  ```
  int[] i = {0,1,2,3}                    // elements in number data type
  string[] s = {"ABC", "DEF", "GHI"}     // elements in string data type
  bool[] bb = {true, false, true}        // elements in boolean data type
  ```

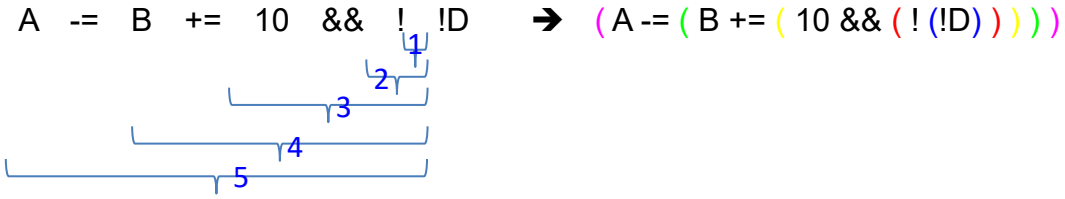
- By utilizing index, the value of specified element can be get, the index is start from 0
  For example
  index 0 1 2 3 4 5 6 7
  array  eight elements in total
  A[0] A[1] A[2] A[3] A[4] A[5] A[6] A[7]
  Valid index values [0] .. [7].
  An error will occur if accessing beyond the range, such as A[8].
- Only one degree array is supported. The maximum index number is 2048.
- The array size may alter according to the return value of functions or assigned values. The maximum element number is 2048. This feature makes array meet the needs of different functions and applications in Network Node.
  For Example:
  ```
  string[] ss = {empty, empty, empty}          // The initial size of string array is 3 elements
  ss = String_Split("A_B_C_D_F_G_H", "_")      // After splitting string, the string array has 7
                                               elements
  len = Length(ss)                             // len = 7
  ss = String_Split("A,B", ",")                // After splitting string, the string array has 2 elements
  len = Length(ss)                             // len = 2
  ```

2.4 Operator Symbols

- The operator table is listed below.
- The calculation follows the precedence of operator first then the associativity.
  For example
  left-to-right associativity



  right-to-left associativity



- The calculation will proceed by the type of the operand.
  1. When both values come as the integer type, the calculation will proceed by the integer type such as
     int var_a = 10
     int var_b = 3
     float var_c = var_a / var_b
     By the operator priority, the calculation goes / first and then =.
     var_a / var_b = 10 / 3 = 3 (both var_a and var_b are integers)
     var_c = 3 (The integer 3 assigns to the floating point number var_c)
  2. When one of the two values comes as the floating-point type, the calculation will proceed by the floating-point type such as
     int var_a = 10
     float var_b = 3
     float var_c = var_a / var_b
     var_a / var_b = 10 / 3 = 3.333333 (for var_b is a floating-point number)
     var_c = 3.333333 (the floating-point 3.333333 assigns to var_c)
     var_c = var_a / 3
     var_a / 3 = 10 / 3 = 3 (both var_a and 3 are integers)
     var_c = 3
     var_c = var_a / 3.0
     var_a / 3.0 = 10 / 3.0 = 3.333333 (for 3.0 is a floating-point)
     var_c = 3.333333

Precedence High to low	Operator	Name	Example	Requirement	associativity
17	++	Postfix increment	i++	Integer variable	left-to-right
	--	Postfix decrement	i--		
	()	Function call	int x = f()		
	[]	Allocate storage	array[4] = 2	Array variable	
16	++	Prefix increment	++i		right-to-

Precedence High to low	Operator	Name	Example	Requirement	associativity
	--	Prefix decrement	--i	Integer	left
	+	Unary plus	int i = +1	Numeric variable, Constant	
	-	Unary minus	int i = -1		
	!	Logical negation	if (!done) …	Boolean	
	~	Bitwise NOT	flag1 = ~flag2	Integer	
14	*	Multiplication	int i = 2 * 4	Numeric variable, Constant	left-to-right
	/	Division	float f = 10.0 / 3.0		
	%	Modulo (integer	int rem = 4 % 3		
13	+	Addition	int i = 2 + 3	Numeric variable, Constant	
	-	Subtraction	int i = 5 - 1		
12	<<	Bitwise left shift	int flags = 33 << 1	Integer variable, Constant	
	>>	Bitwise right shift	int flags = 33 >> 1		
11	<	Less than	if (i < 42) …	Numeric variable, Constant	
	<=	Less than or equal to	if (i <= 42) ...		
	>	Greater than	if (i > 42) …		
	>=	Greater than or equal	if (i >= 42) ...		
10	==	Equal to	if (i == 42) ...		
	!=	Not equal to	if (I != 42) …		
9	&	Bitwise AND	flag1 = flag2 & 42	Integer variable, Constant	
8	^	Bitwise XOR	flag1 = flag2 ^ 42		
7	|	Bitwise OR	flag1 = flag2 | 42		
6	&&	Logical AND	if (condition A && condition B)		
5	||	Logical OR	if (condition A || condition B)		
4	c ? t : f	Ternary conditional	int i = a > b ? a : b		right-to-left
3	=	Basic assignment	int a = b	Left side: Numeric variable Right side: Numeric variable, Constant	
	+=	Addition assignment	a += 3		
	-=	Subtraction	b -= 4		
	*=	Multiplication	a *= 5		
	/=	Division assignment	a /= 2		
	%=	Modulo assignment	a %= 3		

Precedence High to low	Operator	Name	Example	Requirement	associativity
	<<=	Bitwise left shift assignment	flags <<= 2	Left side: Integer variable Right side: Integer variable, Constant	
	>>=	Bitwise right shift assignment	flags >>= 2		
	&=	Bitwise AND	flags &=		
	^=	Bitwise XOR	flags ^=		
	|=	Bitwise OR	flags |= new_flags		

2.5 Data Type Conversion

- Data types can be converted to each other and used in variables/constants or arrays.
- Conversions must be in the same format of the containers such as variable/constant conversions or array conversions. It is not permitted to convert a variable to an array or an array to a variable.

Native type	Conversion type	Example	Result
byte	int	int i = (int)100	i = 100
	float	float f = (float)100	f = 100
	double	double d = (double)100	d = 100
	bool	bool flag = (bool)0	flag = false (0 equals false)
	string	string s = (string)100	s = "100"
int	byte	byte b = (byte)1000	b = 232
	float	float f = (float)1000	f = 1000
	double	double d = (double)1000	d = 1000
	bool	bool flag = (bool)1000	flag = true (non 0 equals true)
	string	string s = (string)1000	s = "1000"
float	byte	byte b = (byte)1.23	b = 1
	int	int i = (int)1.23	i = 1
	double	double d = (double)1.23	d = 1.23
	bool	bool flag = (bool)1.23	flag = true (non 0 equals true)
	string	string s = (string)1.23	s = "1.23"
double	byte	byte b = (byte)1.23	b = 1
	int	int i = (int)1.23	i = 1
	float	float f = (float)1.23	f = 1.23
	bool	bool flag = (bool)1.23	flag = true
	string	string s = (string)1.23	s = "1.23"
bool	byte	byte b = (byte)True	Error
	int	int i = (int)False	Error
	float	float f = (float)true	Error
	double	double d = (double)false	Error
	string	string s = (string)True	s = "true" (shown in lower-case)
string	byte	byte b1 = (byte)"1.23" byte b2 = (byte)"XYZ"	1 Error (Unable to convert "XYZ" to value)
	int	int i = (int)"1.23"	1
	float	float f1 = (float)"1.23" float f2 = (float)"A1"	1.23 Error (Unable to convert "A1" to value)
	double	double d = (double)"1.23"	1.23
	bool	bool flag1 = (bool)"true" bool flag2 = (bool)"false" bool flag3 = (bool)"1.23" bool flag4 = (bool)""	flag1 = true (string "true" as true) flag2= false (string "false" as false) flag3 = true (non-empty string as true) flag4 = false (empty string for false)

- The conversion method of arrays is in accordance with the table above. The conversion is performed for each element in the array.

  string[] ss = {"1.23", "4.56", "0.789"}

```
int[] i_array = (int[])ss          // i_array = {1, 4, 0}
float[] f_array = (float[])ss      // f_array = {1.23, 4.56, 0.789}
```

- Error messages will be returned should the conversions below occur.
  - Fail to convert to numeric correctly such as Booleans (true/false) or non-numeric strings ("XYZ").

```
int value = (int)true              // Error
int value = (int)"XYZ"             // Error
```

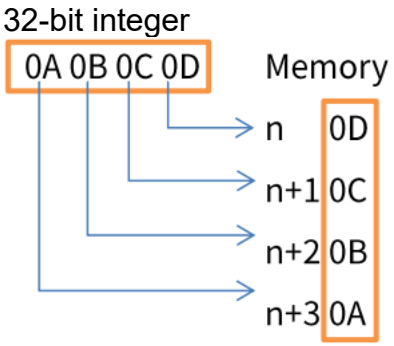
  - Invalid floating-point numbers to convert to floats or doubles such as NaN or Infinity.

```
string   dvalue = "1.79769e+308"
float f = (float) dvalue           // Error 1.79769e+308 is a valid double type and unable to convert to
                                   the float type.
```

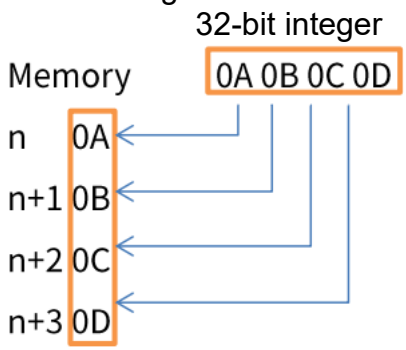
2.6 Endianness and Conversion

Endianness refers to the applications in the memory or the communication networks in which data comes in multiple bytes for the expressions of the order to sort among multiple bytes because the minimal unit comes in bytes.

- Little Endian. Place the low bits of the multibyte at smaller addresses and the high bits at larger ones.



Big Endian. Place the high bits of the multibyte at smaller addresses and the low bits at larger ones.



It is a factor to consider because different orders to sort may cause different conversion results. For example, an integer type is 32 bits. Namely, it occupies 4 bytes. If the int value is 300, the expression in 16-bit is 0x0000012C. If using Little Endian for memory storing or communication networks, the order is

[0]	[1]	[2]	[3]
2C	01	00	00

It fetches 0x0000012C if adopting Little Endian while 0x2C010000 if Big Endian. These are two completely different values, which may cause different results.

TMscript provides a variety of robot programming functions. Among the functions, the conversions of the numeric types, such as int, float, and double, also follow the general endianness rules, which usually apply to file functions, communication-related functions (such as SerialPort, Socket, Modbus), or value-to-byte conversion-related functions. Unless specified otherwise, the function defaults to go by Little Endian. For the string types, it goes by the UTF-8 encoding format that features ASCII character compatibility and fixes endianness without the byte order distinction. For the bool types, it turns the Boolean value true to 1 and false to 0. Refer to the table organized below.

Type	Bit/Byte	Conversion Method	Example	Result
byte	8 bits/1 byte	Little Endian	byte b = 100	0x64
int	32 bits /4 bytes	Little Endian	int i = 300	0x2C 0x01 0x00 0x00
float	32 bits /4 bytes	IEEE-754, Little Endian	float f = 300	0x00 0x00 0x96 0x43
double	64 bits /8 bytes	IEEE-754, Little Endian	double d = 300	0x00 0x00 0x00 0x00 0x00 0xC0 0x72 0x40
bool	bool value	True:1, False:0	bool bf = true	0x01
string	string value	UTF-8	"TM Robot"	0x54 0x4D 0x20 0x52 0x6F 0x62 0x6F 0x74

The value conversion method is an essential basis for communication network applications. Both sides of the applications should recognize the same conversion method to parse the data content correctly. For example,

- **socket_send**("ntd_a", 9000)
  By the function definition, it sends 0x28,0x23,0x00,0x00 (int, Little Endian) to the device ntd_a.
  It gets various values if the receiving device uses different methods to parse. Such as
  int, Big Endian, 0x28 0x23 0x00 0x00 = 673382400
  float, Little Endian, 0x00 0x00 0x23 0x28 = 1.2612E-41
  string, UTF-8, 0x28 0x23 0x00 0x00 = "(#"
  int, Little Endian, 0x00 0x00 0x23 0x28 = 9000
- **socket_send**("ntd_a", (float)9000)
  By the function definition, it sends 0x00,0xA0,0x0C,0x46 (int, Little Endian) to the device ntd_a.
  It gets various values if the receiving device uses different methods to parse. Such as

  int, Big Endian, 0x00 0xA0 0x0C 0x46 = 10488902
  int, Little Endia, 0x46 0x0C 0xA0 0x00 = 1175232512
  float, Big Endian, 0x00 0xA0 0x0C 0x46 = 1.4698082E-38
  string, UTF-8, 0x00 0xA0 0x0C 0x46 = "" // The string ends if encountered 0x00.
  float, Little Endian, 0x46 0x0C 0xA0 0x00 = 9000

2.7 Warning

A warning message will prompt, under the condition listed below.

- Double quotation marks does not placed around the string constant.
  ```
  string s = Hello                // warning  Hello
  ```
- There is single quotation mark inside the string constant.
  ```
  string s0 = "World"
  string s1 = "Hello ‘s0’" // warning  ‘s0’
  ```
- When assigning float value to integer constant, some digits may get lost such as
  ```
  int i = 0
  float f = 1.234
  i = f             // warning  i = 1
  ```
- When assigning value to variables with fewer digits, some digits may get lost such as
  ```
  byte b = 100
  int i = 1000
  float f = 1.234
  double d = 2.345
  b = i             // warning  b = 232     //    byte can contain values from 0 to 255
  f = d             // warning  f = 2.345
  ```
- When assigning a string value to the numeric variable or a numeric value to the string variable, the attempts to convert the string to a number or the number to a string take place automatically. If the conversion is executable, a warning message will prompt, or the project will be stopped by error such as
  ```
  int i = "1234"            // warning  i = 1234
  int j = "0x89AB"          // warning  j = 35243
  int k = "0b1010"          // warning  k = 10
  string s1 = 123           // warning s1 = "123" // Number to string
  string s2 = "123"
  int x = s2                // warning  x = 123 // string to number
  // The following code can be compiled with warning, but will be stopped by error when executing.
  S2 = "XYZ"
  x = s2            // warning // Stop executing by error    // s = "XYZ" cannot be converted to number
  s2 = ""
  x = s2            // warning // Stop executing by error    // s = "" cannot be converted to number
  ```
- String parameters are used as numeric parameters in functions such as
  ```
  Ctrl(0x0A0B0C0D0E) // warning  // 0x0A0B0C0D0E is not int type (over 32bit)
                     // Because there is another syntax, Ctrl(string), the parameter would be applied
                     to Ctrl(string)
  ```

Although the project can still be executed with a warning message, correcting all the errors in a warning message is highly recommended to eliminate unpredictable problems and prevent the project being stopped by errors.

- How to fix the error messages
  1. Use double quotations with the string constants
     ```
     string s = "Hello"
     ```
  2. Use + to link the string constant and the string variable
     ```
     string s0 = "World"
     ```

```
string s1 = "Hello " + s0
```

3. Specify the type clearly for numerical conversions

```
float   f = 1.234
int i = (int) f          // Use (int) for type conversion, i = 1 while processing // It turns the number in floating-point to an integer.
```

3. Script Project Programming

3.1 define

This function defines the global variables in the same project. When the project is running, it prioritizes all the variables in the definition section of the project.

Syntax

```
define
```

For example:

```
define
{
    string text = "Hi TM Robot"
}
```

3.2 main

This function is the first function to call when the project is running, and it is the initial function of the project.

Syntax

```
main
```

For example:

```
define
{
    string text = "Hi TM Robot"
}
main
{
    Display("Hello Techman Robot")
    Display(text)
}
```

The project begins by running the main function as the result of

Hello Techman Robot

Hi TM Robot //Since the dashboard shows the last Display content only, the dashboard content is Hi TM Robot.

TECHMAN ROBOT INC.
5F., No. 58-2, Huaya 2nd Rd., Guishan Dist., Taoyuan City, 333411 , Taiwan

3.3 closestop

When the project is in the halt state without any error, it goes to this function. Not until this function ends will the project stop for sure.

Syntax

```
closestop
```

For example:

```
closestop
{
    IO["ControlBox"].DO = {0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
    // Set the control box DO to Low.
}
```

After the project is running, pressing the STOP button results in the project running the closestop function.



IMPORTANT

This function does not go with motion commands and will close mandatory after 12 seconds of execution at most.

When the closestop function is running, if errors occur (including other errors occur in the system), it will not run the errorstop function but end the project running directly.

For example:

```
main
{
    Exit()
    // Stop the project. Suppose errors did not occur; it runs the closestop function consecutively.
}
closestop
{
    int zero = 0
    int k = 100 / zero  // A dividing by zero error occurred in the closestop function. It ends the project
                        running directly.
    Display("closestop")    // This line does not run due to an error occurring.
```



NOTE

When the project enters the halt state, the TMflow operation interface will depart from the running state , but it will still continue to run the function. Not until this function ends does the project running stop exactly. Before the project stops running, pressing the Play button to run the project returns errors.

3.4 errorstop

When the project is in the halt state with any error, it goes to this function. Not until this function ends will the project stop for sure.

Syntax

```
errorstop
```

For example:

```
main
{
    int zero = 0
    int k = 100 / zero          // A divide by zero error occurs.
}
errorstop
{
    IO["ControlBox"].DO = {0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
    // Set the control box DO to Low.
}
```

After the project is running, the project will generate errors by dividing by zero and go to the errorstop function.



IMPORTANT

This function does not go with motion commands and will close mandatory after 12 seconds of execution at most.

When the errorstop function is running, if errors occur (including other errors occur in the system), it will not run the errorstop function but end the project running directly.

For example:

```
main
{
    int k = 100 / (byte)"0.1"       // A dividing by zero error occurred.
}
errorstop
{
    int k = 100 / (byte)"0.1"       // A dividing by zero error occurred in the errorstop function. It ends
                                    the project running directly.
    Display("errorstop ")   // This line does not run due to an error occurring.
```



NOTE

When the project enters the halt state, the TMflow operation interface will depart from the running state , but it will still continue to run the function. Not until this function ends does the project running stop exactly. Before the project stops running, pressing the Play button to run the project returns errors.

3.5 Customized Function

Inadditional to he built-in define, main, closetop, and errorstop functions, Script projects provide customized functions for users. The customized Show() function below does not take any parameters nor return any values. (It defines the return type as void.)

For example:

```
main
{
    Show()   // Call the customized function Show().
}
void Show()
{
    Display("Hello TM AI Cobot")
}
```

Customized functions support parameter input and output. There are two functions customized in the example below. The Add() can add up the two values users input and return the added up result; the Sub() subtracts the two values users input and return the subtraction result. Note that as long as the return value is not a void type, it requires to return the value of the same type as the definition. Such as the Add() adopts the float type, and the returned variable must be the float type as well.

For example:

```
main
{
    string Add_Result = "Add:" + Add(5.9, 3.6)
    string Sub_Result = "Sub:" + Sub(5.9, 3.6)
    Display("Green", "Yellow", "Result", Add_Result + newline + Sub_Result)
}
float Add(float augend, float addend)
{
    float result = augend + addend
    return result
}
float Sub(float minuend, float subtrahend)
{
    float result = minuend - subtrahend
    return result
}
```



IMPORTANT

If the function defines the return type, it must return with the same type. If the definition is void, it is not required to use return.

3.6 Comment

Use part of the code as a comment. The compiler ignores the commented code. Users can comment a single line or multi-lines on the code not to execute.

- **Single Line Comment**

Uses can comment at the very beginning of the code with // to complete a single-line comment, as shown below. The compiler will ignore a = a + 1.

```
main
{
    int a = 0
    // a = a + 1
}
```

- **Multi Line Comment**

Users can comment with /* as the start of the comment and */ as the end of the comment. As below, between /* and */, the compiler will ignore int a = 0 and a = a + 1.

```
main
{
    /*
    int a = 0
    a = a + 1
    */
}
```

3.7 Variable

By variable declaration, users can proceed with applications such as calculation, reading and writing, and parameter conveyance. Variables come with the global variables and the local variables.



IMPORTANT
Variables are case sensitive such as TMrobot and TMROBOT are two different variables.

- **Project Variable**

Once declared a variable in the definition section, the variable is a global variable in the project. This variable can be read and written in functions of the same project. As shown below, if the define declares the variable b, and the main function runs, it calls Test1() first and sets the variable as 20. When it displays the variable value next, it gets b as 20 for the last set value.

```
define
{
    int b = 0
}
main
{
    Test1()
    Display("B Value: " + b)
}
void Test1()
{
    b = 20
}
// B Value: 20
```



IMPORTANT
The project variables in the project are different from the global variables in the global variable manager of the robot. The global variables in the project indicate they can operate across functions in the project. Other than across functions in the project, the global variables in the global variable manager of the robot operate across functions of different projects.



IMPORTANT
Users can create global variables in the global variable manager in the TMflow operation interface only but not with TMscript syntax.

- **Local Variable**

If variables are declared outside of the definition section such as main, closestop, errorstop, and customized functions, the variables are local variables and good in the functions only.

```
int sum(int s)
{
    int a = 0
}
// Defined two variables int s and int a. When sum() ends, the two local variable are gone.
```

Neither can variable names in the definition section of the same function be duplicated, nor can they replicate with the global variables in the define section and in the global variable manager of the robot.

```
define
{
    int b = 0
    string g_s1 = ""    // Suppose the global variable manager defines g_s1; there will be variable
                        duplication.
}
void sum(int s)
{
    int a = 0
    int b = 1       // Duplicated with int b in define.
    float a = 0     // Duplicated with int a.
}
```

Local variables are independent of different function sections. Such declared a variable a in both Test1() and Test2(). Because of being in disparate functions, the two variables are independent and valid only in each function section.

```
void Test1()
{
    int a = 0
}
void Test2()
{
    int a = 2
}
```

The scope of the local variables can be valid in a top-down coverage. Users can also declare variables in the conditional statement or the loop statement, and the variables are present in the conditional statement or the loop statement. The variables are absent from the outside of the scope. Therefore, once the variables exit from the scope, the variables will release the variable data. For variables declared by the class, such as SerialPort, Socket, and Modbus, the variables will close the devices.

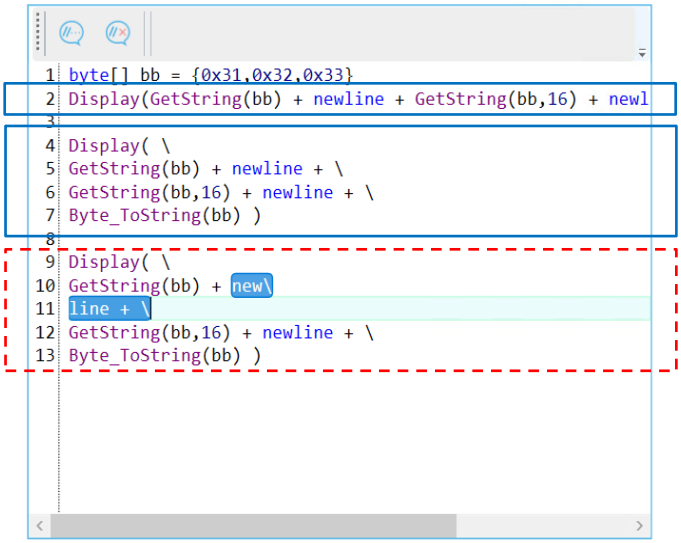
```
void Test1()
{
        int a = 10                                  variable a effective scope
        if (a > 5)
        {                                           variable b effective scope
            int b = 20
            Display("A Value: " + a)
        }
        Display("B Value: " + b)      // Warning. b will be taken as a string instead of a variable.
}
void Test2()
{
        if (true)
        {                                                   variable bbb effective scope
            Socket bbb = "127.0.0.1",12345
            socket_open("bbb")
            Sleep(5000)
        } // After a 5-second waiting, variable bbb will be released for exiting the f conditional statement
        scope and close the connection.
        Sleep(10000)
}
```

In the Flow project, if users want to create a global variable in the project, they need to do it in the variable manager or device manager. Users cannot create a global variable in the flow project with the Script. Moreover, because each process node is an independent function, including the Script node, if declaring variables in the node, they are all local variables. When exiting the node, the variables in the node will no longer exist, and the variable data will be released.

3.8 Multi-Line Input

Once an expression to input goes with more contents, it is a disadvantage to maintain or debug. Users can add \ at the end of the line to fulfill the multi-line input of consecutive contents. The multi-line input contents will be taken as an expression in the same line until there is no \, and it goes with a new line character at the end.

While using multi-line input, it is still required to maintain the correctness of wording but not to use \ at random for multi-line continuations among words.



//Beyond the viewable scope, which requires scrolling to read the content.
//Use multi-line input, \, to continue for easy content viewing.

//Incorrect multi-line put, where newline is a reserved word and cannot be cut.

3.9 Conditional Statements

During the project running, it might be necessary to consider different approaches, such as task fails, function, and communication errors, to various situations. Users can use conditional statements to adopt different paths to the result values at this time. Two conditional statements, if and switch, are available so far.

3.9.1 if

The if statement can judge the conditional expression in the brackets. It enforces statement 1 if the condition meets.

```
if (conditional expression)
{
    statement 1        // the condition satisfies.
}
```

Or vice versa. If the condition satisfies, it goes to statement 1. If not, it goes statement 2.

```
if (conditional expression)
{
    statement 1        // the condition satisfies.
}
else
{
    statement 2        // the condition not satisfies.
}
```

Users can also check more possibilities with the if .. else if .. else statement to judge the condition 1, 2, 3, and the last otherwise condition in sequence.

```
if (conditional expression 1)
{
    statement 1        // the condition 1 satisfies.
}
else if (conditional expression 2)
{
    statement 2        // the condition 2 satisfies.
}
else if (conditional expression 3)
{
    statement 3        // the condition 3 satisfies.
}
else
{
    statement 4        // the condition 1, 2, and 3 not satisfy at all.
}
```

Take the example below. If the Score is 100, it displays "Full Score." Between 60 and 99,

"Excellent"; otherwise, "Failed." Users can write the condition with the if statement.

```
void Test1()
{
    int Score = 65
    if (Score == 100)
    {
        Display("Green", "Yellow", "Full Score", "")
    }
    else if (Score >= 60)
    {
        Display("Green", "Yellow", "Excellent", "")
    }
    else
    {
        Display("Red", "Yellow", "Failed", "")
    }
}
// Excellent
```



NOTE
== of if (Score==100) stands for comparison, and = of int Score = 65, assignment.

The criteria to evaluate conditional expressions are as follows, but boolean values have much to recommend for evaluation.

- Boolean values true or True for the condition satisfies, false or False, not satisfies.
- Numeric values non-zeros for the condition satisfies, zeros, not satisfies.
- String values true or True for the condition satisfies, other string values, not satisfies.

3.9.2 switch

The switch statement is similar in condition judgment to the if statement. The switch statement goes with the other way of writing for similar conditions.

```
switch (variable or expression)
{
    case condition 1 satisfies
        statement 1          // the condition 1 satisfies.
        break
    case condition 2 satisfies
        statement 2          // the condition 2 satisfies.
        break
    default
        statement 3          // the condition 1 and 2 both not satisfy.
        break
}
```

As the example below, it can match various results by the content value of the variable.

```
void Test1()
{
    string di_st = (string)IO["ControlBox"].DI[1] + (string)IO["ControlBox"].DI[0]
    switch (di_st)
    {
        case "00"
            Display("DI[0]=0, DI[1]=0")
            break
        case "01"
            Display("DI[0]=1, DI[1]=0")
            break
        case "10"
            Display("DI[0]=0, DI[1]=1")
            break
        default
            Display("DI[0]=1, DI[1]=1")
            break
    }
}
// DI[0]=0, DI[1]=0
```

Besides, the switch statement supports expressions. Like the example below, if the Score is 100, it displays "Full Score." Between 60 and 99, "Excellent"; otherwise, "Failed."

```
void Test1()
{
    int Score = 65
    switch (Score)
    {
        case >= 100
            Display("Green", "Yellow", "Full Score", "")
            break
        case >= 100-40
            Display("Green", "Yellow", "Excellent", "")
            break
        default
            Display("Red", "Yellow", "Failed", "")
            break
    }
}
// Excellent
```

The differences from the if statement is

- The switch statement retrieves the value once and compares the result value multiple times, and the if statement retrieves every time it compares. This makes the switch's judgment on the DI status more accurate.

- As the reason above, the switch statement cannot apply to the conditions of different natures, and the if statement can. Such as

```
void Test1()
{
	int Payload = 4
	int Length = 130
	if (Payload > 4)
	{
		Display("Green", "Yellow", "Payload", "")
	}
	else if (Length > 70)
	{
		Display("Green", "Yellow", "Length", "")
	}
	// This statement of if .. else if .is unable to be written with the switch statement.
}
```

3.10 Loop Statements

During the project running, it may be necessary to repeatedly calculate certain values or check whether the conditions are comprehended. In these cases, it requires the loop statements that go on iterative processing the code in the statement until the condition is comprehended. Three loop statements, for, while, and do-while, are available so far.

3.10.1 for

The for loop syntax comprises four sections, the initialization section, the loop condition section, the statement, and the iterative operation section.

```
for (the initialization section; the loop condition section; the iterative operation section)
{
    statement
}
```

The execution sequence is as below.

1. The initialization section: When it goes to the for syntax, it executes the initialization section one time. It is usually used to declare variables. (The variables are the local variables in the for syntax.)
2. The loop condition section: It decides whether to go on the for loop condition execution. Once comprehended (true) or not existed, it goes on the for loop execution. It exits the for loop until the condition is not comprehended (false).
3. The execution statement: The statement to execute.
4. The iterative operation section: After the statement execution, it executes the iterative operation section once and then goes back to the loop condition section for the condition judgment.

The example is a basic application of the for loop. It adds the number from 0 to the input K value.

```
int sum(int k)
{
    int result = 0
    for (int i = 0; i < k; i++)
    {
        result += i
    }
    return result
}
```

Users can use multiple for loops together. The example presents the multiplication table by the for loop.

```
void Test1()
{
    string result = ""
    for (int i = 1; i <= 9; i++)
```

```
        {
            for (int j = 1; j <= 9; j++)
            {
                result += j + "X" + i + "=" + i * j + " "
            }
            result += newline
        }
        Display("Green", "Yellow", "multiplication table", result)
    }
```

Users can adopt the four sections in for loop optionally.

```
    void Test1()
    {
        int i = 0
        for (i = 3; i < 4; )
            i++
        // i = 3
        // i < 4        // i++          // i = 4
        // i < 4        // false, exit for
        for ( ; i < 5; i++)
        {
        }
        // Since the value of i is not reset, it will continue using i =4.
        // i < 5        //              // i++, i = 5
        // i < 5        // false, exit for

        for ( ; ; )                 // Execution continues because the loop condition section does not exist.
        {
            // …
        }
    }
```

3.10.2 while

The while loop comes with one boolean conditional expression only. Once the condition satisfies (true), it executes the statement until the condition does not satisfy (false) and exit the while loop. Therefore, the number of the while loop execution is zero or more, and it may exit for the condition does not satisfy at the first time.

```
    while (conditional expression )
    {
        statement
    }
```

The example below adopts an arithmetic progression to count the number from 0, 1, 2, 3, …, and N until the total is 500500 and gets the value of N.

```
        void Test1()
```

```
{
    int sum = 0
    int N = 0
    while (sum != 500500)
    {
        N += 1
        sum += N
    }
    Display(N)
}
// N = 1000
```

3.10.3 do while

The syntax of the do while loop is similar to that of the while loop. The while loop checks whether if the condition satisfies first before executing statements in the code block; however, the do while loop executes the command first and then check whether if the condition satisfies. Accordingly, the do while loop executes the statement one time at least.

```
do
{
    statement
} while (conditional expression )
```

For example as below, if using the do while loop, it displays Hello TM Robot.

```
void Test1()
{
    int result = 0
    do
    {
        Display("Hello TM Robot")
    } while(result > 5)
}
```

On the contrary, if using the while loop, it does not display any result.

```
void Test1()
{
    int result = 0
    while(result > 5)
    {
        Display("Hello TM Robot")
    }
}
```

3.11 Branching Statements

3.11.1 break

It applies to exit the last loop statement of for, while, or do while without satisfying the loop condition and exit. As the example below, once i is larger than 10, it exits and ends the for loop.

```
int sum(int k)
{
    int result = 0
    for (int i = 0; i < k; i++)
    {
        if (i > 10)
        {
            break
        }
        result += i
    }
    return result
}
void Test1()
{
    string result = ""
    for (int i = 1; i <= 9; i++)
    {
        for (int j = 1; j <= 9; j++)
        {
            result += j + "X" + i + "=" + i * j + " "
            if (j > 4) break
        }
        result += newline
    }
    Display("Green", "Yellow", "multiplication table", result)
}
```

Exit the closest for i loop directly.

Exit the closest for j loop directly.

3.11.2 continue

It applies to the loop statements of for, while, and do while, but it is different from the break statement in that it ends the closest and current loop and begins the next loop without exiting the loop. As the example below, if it is an even number, it ends the current loop directly and begins the next loop. So, it registers odd numbers only.

```
void Test1()
{
    string result = ""
    for (int i = 0; i < 10; i++)
    {
        if (i % 2 == 0)
        {
            continue
        }
        result += i + ", "
    }
    Display("Odd value: " + result)
}
// Odd value: 1, 3, 5, 7, 9
```

Ends the current loop and goes back to the next loop.

3.11.3 return

The return statement ends the statement execution in the function and returns the value to the function caller. For example,

```
main
{
    int num = sum(10)                    // num = 3
    Display(num)
}
int sum(int k)
{
    int result = 0
    for (int i = 0; i < k; i++)
    {
        if (i == 3) return result  // Once i == 3, it returns the result directly without further statement
                                   executions.
        result += i
    }
    return result
}
```

3.12 Thread

During the process of project programming, when it comes to asynchronous parallel operations, users need to use threads. By creating new threads for operations, users can make the project go with the multi-tasking concept. However, users also have to pay attention to no priority among threads in execution, and each operates independently when with multiple ones.

The main function to be called first during the project running acts as a thread also. What's different about this thread from others is that the main function called by this thread and other customized functions called in the main function come with the privilege to call robot motion functions. Calling robot motion functions is not granted to other newly created threads. This is to ensure the consistency of the robot motion process because each thread processes independently. It is easy to confuse or interrupt the robot motion processes if granting other threads to use the robot motion functions.

Other than the other threads, the main thread comes with the privilege of the robot motion function call. The other newly created threads are not allowed for the robot motion function call. It is to ensure the consistency of the robot motion process. Since each thread operates independently, if others are for the robot motion function call, it gets the robot motion to be interrupted or confused easily.

In addition to the privilege of the robot motion function call, users can set the thread to whether continuously execute or not, which means if the project pausethread will be influenced by the or not. Once setting the thread to continuous execution, even if the project pauses, this thread continues to operate. Such a setting is suitable for communication applications.

When the thread-to-use works in a loop (with the loop statement), adding the additional sleep function to free up the thread-occupied CPU usage is requisite and recommended while working around threads, which is an attention must because excessive CPU usage may result in poor execution efficiency.

3.12.1 ThreadRun()

Create a new thread and use the new one to execute the statement. The previous one will continue proceeding.

Syntax 1

int **ThreadRun**(
    ?,
    bool
)

Parameters

?	statement or customized function
bool	Whether the thread will continue the execution without being paused
true	continue the execution without being paused
false	to be paused (default)

Return

int	return the ID of the newly created thread.

> 0 created successfully
<= 0 created unsuccessfully
*The ID of the newly created thread goes by the system, and it is not a fixed value. The thread number in the process will not be repetitive, but the number might be recurring once the thread stops.

Syntax 2

int **ThreadRun**(
?
)

Note

Same as Syntax 1. The default is to set whether the thread will continue the execution to false.

3.12.2 ThreadID()

Retrieve the ID of the current thread.

Syntax 1

int **ThreadID**(
)

Parameter

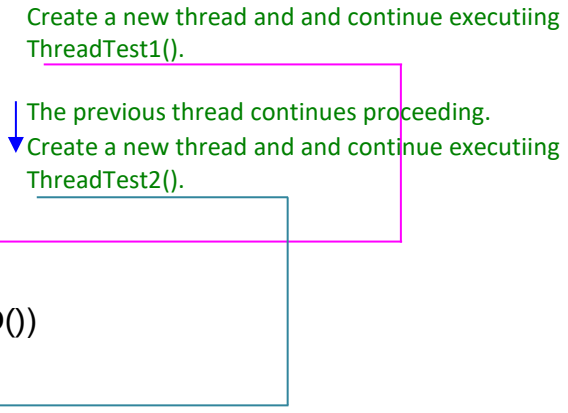
void No parameter

Return

int return the ID of the thread

Note

```
main
{
    int tid = ThreadRun(ThreadTest1(), false)
    Sleep(1000)
    ThreadRun(ThreadTest2(tid), true)
}
void ThreadTest1()
{
    Display("Hello ThreadTest1() " + ThreadID())
}
void ThreadTest2(int k)
{
    Display("Hello ThreadTest2() " + ThreadID() + " " + k)
}
// Hello ThreadTest1() 18
// Hello ThreadTest2() 61 18
```



The following description denotes the execution order of creating new threads for running statements.

```
main
{
    int tid = ThreadID()
```

```
        ThreadRun(ThreadTest3(tid, ThreadID()), false)
    }
    void ThreadTest3(int k1, int k2)
    {
        Display("Hello ThreadTest3() " + ThreadID() + " " + k1 + " " + k2)
    }
    // Hello ThreadTest3() 65 47 65
```

- The execution order goes by

1. Retrieve the thread ID in the main thread and assign the value the local variable tid.
2. Create a new thread and execute the statement of ThreadTest3(tid, ThreadID()).
3. As tid is a local variable, the value of tid is available to lead in.
4. Since ThreadID() is a function and it uses a new thread for the function call, the obtained thread ID will be different from the tid.
5. Again, call the ThreadTest3() function, and lead it and the obtained thread ID into k1 and k2 in the function, respectively
6. Call the ThreadID() function in the ThreadTest3() function to get the thread ID. Because it is the same thread as the ThreadTest3() function is in, k2 will go with the same ID and k1 with a different ID.

3.12.3 ThreadState()

Retrieve the status of the assigned thread ID.

Syntax 1

int **ThreadState**(
    int
)

Parameter

int	thread ID	

Return

int	return the status of the dedicate thread	
	-1	The thread does not exist.
	0	The thread is in execution.
	1	The thread is requesting to stop.
	2	The thread stopped.

Syntax 2

int **ThreadState**(
)

Note

Same as Syntax 1. The default is to set the thread ID with the current thread ID of the function call.

3.12.4 ThreadExit()

Request the assigned thread ID to stop execution.

Syntax 1

```
int ThreadExit(
    int
)
```

Parameter

int	thread ID	

Return

int	return the result of requesting the assigned thread to stop	
	-1	The thread does not exist.
	0	The requested thread stopped execution.

Syntax 2

```
int ThreadExit(
)
```

Note

Same as Syntax 1. The default is to set the thread ID with the current thread ID of the function call.

```
define
{
    int tid = 0
}
main
{
    int st = 0
    int t4 = ThreadRun(ThreadTest4())
    do
    {
        Sleep(100)
        st = ThreadState(t4)
        Display("t4 " + st)      // t4 0
    } while (st != 2)          // Use the loop statement to wait for the thread t4 to stop.
    // Since there is no loop in ThreadTest4, the thread stops after the execution ends.
    Display("t4 " + st + " " + tid)      // t4 2 51
}
void ThreadTest4()
{
    Sleep(1000)
    tid = ThreadID()
}


define
{
    string title = ""
}
main
{
    int st = 0
    title = "t5 " + st                    // t5 0
```

```
    int t5 = ThreadRun(ThreadTest5())
    bool flag = WaitFor((st = ThreadState(t5)) == 2, 1000)
    // Use WaitFor to wait for the thread t5 to stop.
    title = "t5 " + st + " " + flag          // t5 0 false
    // Since there is a loop in ThreadTest5, the thread will not stop.
    // Therefore, WaitFor quits after a 1000 ms timeout. So, flag = false.
    Sleep(1000)
    if (flag == false)
    {
        ThreadExit(t5)                  // Request the thread t5 to quit.
    }
    flag = WaitFor((st = ThreadState(t5)) == 2, 1000)
    // Use WaitFor to wait for the thread t5 to stop.
    // Since the system requested the thread t5 to stop, the WaitFor condition sustains.
    Display("t5 " + st + " " + flag, "Hello main() " + ThreadID())// t5 2 true
}
void ThreadTest5()
{
    while (true)    // the loop statement
    {
        Display(title , "Hello ThreadTest5() " + ThreadID())
        Sleep(100)
        // While using the loop statement, applying the additional sleep function is recommended to free
        up the thread-occupied CPU usage.
    }
}
```

4. General Functions

4.1 Byte_ToInt16()

Transform the first two bytes of the assigned byte array to integer, and returns in int type.

Syntax 1

int **Byte_ToInt16**(
    byte[],
    int,
    int
)

Parameters

byte[]	Byte array	
int	Byte array follows the Little Endian or Big Endian	
	0	Little Endian (Default)
	1	Big Endian
int	Transfer to signed int16 (Signed Number) or unsigned int16 (Unsigned Number)	
	0	signed int16 (Default)
	1	unsigned int16

Return

int — A signed or unsigned int16 formed by 2 bytes beginning at index [0]. Because only 2 bytes is needed, the index of byte array will be [0][1]. If the data is not long enough, it would be filled to 2 bytes before transforming.

Note

```
byte[] bb1 = {0x90, 0x01, 0x05}
byte[] bb2 = {0x01}
// Cause bb2[] does not fill 2 bytes. It would be filled to 2 bytes before transforming.

value = Byte_ToInt16(bb1, 0, 0)    // 0x0190 value = 400
value = Byte_ToInt16(bb1, 0, 1)    // 0x0190 value = 400
value = Byte_ToInt16(bb1, 1, 0)    // 0x9001 value = -28671
value = Byte_ToInt16(bb1, 1, 1)    // 0x9001 value = 36865
value = Byte_ToInt16(bb2, 0, 0)    // 0x0001 value = 1
value = Byte_ToInt16(bb2, 0, 1)    // 0x0001 value = 1
value = Byte_ToInt16(bb2, 1, 0)    // 0x0100 value = 256
value = Byte_ToInt16(bb2, 1, 1)    // 0x0100 value = 256
```

Syntax 2

int **Byte_ToInt16**(
    byte[],
    int
)

Note

Similar to Syntax 1 with return value as signed int16

Byte_ToInt16(bb1, 0) => **Byte_ToInt16**(bb1, 0, 0)

Syntax 3

int **Byte_ToInt16**(

byte[]
)

Note

Similar to Syntax 1 with little endian input and return value as signed int16

Byte_ToInt16(bb1) => **Byte_ToInt16**(bb1, 0)

4.2 Byte_ToInt32()

Transform the first four bytes of byte array to integer, and return in int type.

Syntax 1

int **Byte_ToInt32**(
    byte[],
    int
)

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian

Return

int	An unsigned int32 formed by 4 bytes beginning at index [0]. Because only 4 bytes is needed, the index of byte array will be [0][1][2][3]. If the data is not long enough, it would be filled to 4 bytes before transforming.

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03}
// Cause bb2[] does not fill 4 bytes. It would be filled to 4 bytes before transforming.

value = Byte_ToInt32(bb1, 0)  // 0x4F030201 value = 1325597185
value = Byte_ToInt32(bb1, 1)  // 0x0102034F value = 16909135
value = Byte_ToInt32(bb2, 0)  // 0x00030201 value = 197121
value = Byte_ToInt32(bb2, 1)  // 0x01020300 value = 16909056
```

Syntax 2

int **Byte_ToInt32**(
    byte[]
)

Note

Similar to Syntax 1 with little endian input

Byte_ToInt32(bb1) => **Byte_ToInt32**(bb1, 0)

4.3 Byte_ToFloat()

Transform the first four bytes of byte array to floating-point number, and return in floating-point type.

Syntax 1

float **Byte_ToFloat**(
    byte[],
    int
)

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian

Return

float A floating-point number formed by 4 bytes beginning at index [0].
Because only 4 bytes is needed, the index of byte array will be [0][1][2][3]. If the data is not long enough, it would be filled to 4 bytes before transforming.

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03} // Cause bb2[] does not fill 4 bytes. It would be filled to 4 bytes before transforming.
value = Byte_ToFloat(bb1, 0)  // 0x4F030201 value = 2.1979466E+09
value = Byte_ToFloat(bb1, 1)  // 0x0102034F value = 2.3879603E-38
value = Byte_ToFloat(bb2, 0)  // 0x00030201 value = 2.76225E-40
value = Byte_ToFloat(bb2, 1)  // 0x01020300 value = 2.387938E-38
```

Syntax 2

float **Byte_ToFloat**(
    byte[]
)

Note

Similar to Syntax 1 with little endian input
Byte_ToFloat(bb1) => **Byte_ToFloat**(bb1, 0)

4.4 Byte_ToDouble()

Transform the first eight bytes of byte array to floating-point number, and return in double type.

Syntax 1

double **Byte_ToDouble**(
    byte[],
    int
)

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian

Return

double	A floating-point number formed by 8 bytes beginning at index [0]. Because only 8 bytes is needed, the index of byte array will be [0][1][2][3][4][5][6][7]. If the data is not long enough, it would be filled to 8 bytes before transforming.

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x4F, 1} // Cause bb1[] does not fill 8 bytes. It would be filled to 8 bytes before transforming.
byte[] bb2 = {0x01, 0x02, 0x03}// Cause bb1[] does not fill 8 bytes. It would be filled to 8 bytes before transforming.
value = Byte_ToDouble(bb1, 0) // 0x000000014F030201 value = 2.7769278203E-314
value = Byte_ToDouble(bb1, 1) // 0x0102034F01000000 value = 8.20840179153173E-304
value = Byte_ToDouble(bb2, 0) // 0x0000000000030201 value = 9.73907E-319
value = Byte_ToDouble(bb2, 1) // 0x0102030000000000 value = 8.207852449261364E-304
```

Syntax 2

double **Byte_ToDouble**(
    byte[]
)

Note

Similar to Syntax 1 with little endian input

Byte_ToDouble(bb1) => **Byte_ToDouble**(bb1, 0)

4.5 Byte_ToInt16Array()

Transform byte array to integer every 2 bytes, and return in int[] type.

Syntax 1

int[] **Byte_ToInt16Array**(
    byte[],
    int,
    int
)

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian
int	Transfer to signed int16 (Signed Number) or unsigned int16 (Unsigned Number)
0	signed int16 (Default)
1	unsigned int16

Return

int[] A integer array formed by every 2 bytes of byte array beginning at index [0]

Note

```
byte[] bb1 = {0x90, 0x01, 0x02, 0x03, 0x04}
// When the remaining part does not fill 2 byte, it would be filled to 2 bytes before transforming.

byte[] bb2 = {1, 2, 3, 4}

value = Byte_ToInt16Array(bb1, 0, 0) // {0x0190, 0x0302, 0x0004} value = {400, 770, 4}
value = Byte_ToInt16Array(bb1, 0, 1) // {0x0190, 0x0302, 0x0004} value = {400, 770, 4}
value = Byte_ToInt16Array(bb1, 1, 0) // {0x9001, 0x0203, 0x0400} value = {-28671, 515, 1024}
value = Byte_ToInt16Array(bb1, 1, 1) // {0x9001, 0x0203, 0x0400} value = {36865, 515, 1024}

value = Byte_ToInt16Array(bb2, 0, 0) // {0x0201, 0x0403} value = {513, 1027}
value = Byte_ToInt16Array(bb2, 0, 1) // {0x0201, 0x0403} value = {513, 1027}
value = Byte_ToInt16Array(bb2, 1, 0) // {0x0102, 0x0304} value = {258, 772}
value = Byte_ToInt16Array(bb2, 1, 1) // {0x0102, 0x0304} value = {258, 772}
```

Syntax 2

int[] **Byte_ToInt16Array**(
    byte[],
    int
)

Note

Similar to Syntax 1 with return value as signed int16

Byte_ToInt16Array(bb1, 0) => **Byte_ToInt16Array**(bb1, 0, 0)

Syntax 3

int[] **Byte_ToInt16Array**(
    byte[]

)

Note

Similar to Syntax 1 with little endian input and return value as signed int16
Byte_ToInt16Array(bb1) => **Byte_ToInt16Array**(bb1, 0)

4.6 Byte_ToInt32Array()

Transform byte array to integer every 4 bytes, and return in int[] type

Syntax 1

int[] **Byte_ToInt32Array**(
    byte[],
    int
)

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian

Return

int[] A integer array formed by every 4 bytes of byte array beginning at index [0]

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x04, 0x05}
// When the remaining part does not fill 4 byte, it would be filled to 4 bytes before transforming.

byte[] bb2 = {1, 2, 3, 4}

value = Byte_ToInt32Array(bb1, 0) // {0x04030201, 0x00000005} value = {67305985, 5}
value = Byte_ToInt32Array(bb1, 1) // {0x01020304, 0x05000000} value = {16909060, 83886080}
value = Byte_ToInt32Array(bb2, 0) // {0x04030201} value = {67305985}
value = Byte_ToInt32Array(bb2, 1) // {0x01020304} value = {16909060}
```

Syntax 2

int[] **Byte_ToInt32Array**(
    byte[]
)

Note

Similar to Syntax 1 with little endian input.

Byte_ToInt32Array(bb1) => **Byte_ToInt32Array**(bb1, 0)

4.7 Byte_ToFloatArray()

Transform byte array to integer every 4 bytes, and return in float[] type.

Syntax 1

```
float[] Byte_ToFloatArray(
    byte[],
    int
)
```

Parameters

byte[]	The input byte array
int	The input byte array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian

Return

float[] A floating-point number array formed by every 4 bytes of byte array beginning at index [0]

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x04, 0x05}
                // When the remaining part does not fill 4 byte, it would be filled to 4 bytes before
                   transforming.
byte[] bb2 = {1, 2, 3, 4}

value = Byte_ToFloatArray(bb1, 0)
                // {0x04030201, 0x00000005} value = {1.5399896E-36,7E-45}
value = Byte_ToFloatArray(bb1, 1)
                // {0x01020304, 0x05000000} value = {2.3879393E-38,6.018531E-36}
value = Byte_ToFloatArray(bb2, 0) // {0x04030201} value = {1.5399896E-36}
value = Byte_ToFloatArray(bb2, 1) // {0x01020304} value = {2.3879393E-38}
```

Syntax 2

```
float[] Byte_ToFloatArray(
    byte[]
)
```

Note

Similar to Syntax 1 with little endian input

Byte_ToFloatArray(bb1) => **Byte_ToFloatArray**(bb1, 0)

4.8 Byte_ToDoubleArray()

Transform byte array to double every 8 bytes, and return in double[] type.

Syntax 1

double[] **Byte_ToDoubleArray**(
    byte[],
    int
)

Parameters

byte[] The input byte array

int The input byte array follows Little Endian or Big Endian

0 Little Endian (Default)

1 Big Endian

Return

double[] A floating-point number array formed by every 8 bytes of byte array beginning at index [0]

Note

```
byte[] bb1 = {0x01, 0x02, 0x03, 0x04, 0x05}   // When the remaining part does not fill 8 byte, it would be filled to 8 bytes before transforming.
byte[] bb2 = {1, 2, 3, 4}      // When the remaining part does not fill 8 byte, it would be filled to 8 bytes before transforming.

value = Byte_ToDoubleArray(bb1, 0) // {0x0000000504030201} value = {1.064323253E-313}
value = Byte_ToDoubleArray(bb1, 1)
// {0x0102030405000000} value = {8.207880398492326E-304}

value = Byte_ToDoubleArray(bb2, 0) // {0x0000000004030201} value = {3.3253575E-316}
value = Byte_ToDoubleArray(bb2, 1)
// {0x0102030400000000} value = {8.207880262684596E-304}
```

Syntax 2

double[] **Byte_ToDoubleArray**(
    byte[]
)

Note

Similar to Syntax 1 with little endian input

Byte_ToDoubleArray(bb1) => **Byte_ToDoubleArray**(bb1, 0)

4.9 Byte_ToString()

Transform byte array to string

Syntax 1

```
string Byte_ToString(
    byte[],
    int
)
```

Parameters

byte[]	The input byte array
int	The character encoding rules applied to input byte array
0	UTF8 (Default) (0x00 END)
1	HEX BINARY
2	ASCII (0x00 END)

Return

string	String formed by byte array. The transformation begins from index [0].

Note

byte[] bb1 = {0x31, 0x32, 0x33, 0x00, 0x4F, 1}

byte[] bb2 = {0x01, 0x54, 0x4D, 0x35, 0xE6, 0xA9, 0x9F, 0xE5, 0x99, 0xA8, 0xE4, 0xBA, 0xBA}

```
value = Byte_ToString(bb1, 0) // value = "123"    (UTF8 stop at 0x00)
value = Byte_ToString(bb1, 1) // value = "313233004F01"
value = Byte_ToString(bb1, 2) // value = "123"    (ASCII stop at 0x00)
value = Byte_ToString(bb2, 0) // value = "\u01TM5機器人"    (UTF8)
value = Byte_ToString(bb2, 1) // value = "01544D35E6A99FE599A8E4BABA"
value = Byte_ToString(bb2, 2) // value = "\u01TM5??????????"    (ASCII)
```

* \u01 represents the SOH control character, not the string value.

Syntax 2

```
string Byte_ToString(
    byte[]
)
```

Note

Similar to Syntax 1 with UTF8 character encoding rules

Byte_ToString(bb1) => **Byte_ToString**(bb1, 0)

4.10 Byte_Concat()

Concatenate two byte arrays, or concatenate one array with a byte value.

Syntax 1

byte[] **Byte_Concat**(
byte[],
byte
)

Parameters

byte[] The input byte array
byte The byte value concatenated after the byte array

Return

byte[] The byte array formed by the input byte array and byte value

Note

```
byte[] bb1 = {0x31, 0x32, 0x33, 0x00, 0x4F, 1}

value = Byte_Concat(bb1, 12) // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x0C}
```

Syntax 2

byte[] **Byte_Concat**(
byte[],
byte[]
)

Parameters

byte[] The input byte array1
byte[] The input byte array2, would be concatenated to the end of array1

Return

byte[] Byte array formed from concatenating input arrays.

Note

```
byte[] bb1 = {0x31, 0x32, 0x33, 0x00, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03}

value = Byte_Concat(bb1, bb2)
        // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x01, 0x02, 0x03}
```

Syntax 3

byte[] **Byte_Concat**(
byte[],
byte[],
int
)

Parameters

byte[] The input byte array1
byte[] The input byte array2, would be concatenated after the end of array1
int The number of element in array2 to be concatenated
0..the length of array2 Valid number
<0 Invalid. Length of array2 will be applied instead.

> the length of array2 Invalid. Length of array2 will be applied instead.

Return

byte[] Byte array formed from concatenating input arrays.

Note

```
byte[] bb1 = {0x31, 0x32, 0x33, 0x00, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03}

value = Byte_Concat(bb1, bb2, 2)        // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x01, 0x02} // Concatenate only 2 elements from array2
value = Byte_Concat(bb1,   bb2, -1)     // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x01, 0x02, 0x03} // -1 is invalid value
value = Byte_Concat(bb1, bb2, 10)       // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x01, 0x02, 0x03} // 10 exceeds the array size

                                        // Length() can be utilized to acquire the array size
value = Byte_Concat(bb1, bb2, Length(bb2))
                                        // value = {0x31, 0x32, 0x33, 0x00, 0x4F, 0x01, 0x01, 0x02, 0x03}
```

Syntax 4

```
byte[] Byte_Concat(
    byte[],
    int,
    int,
    byte[],
    int,
    int
)
```

Parameters

byte[] The input byte array1

int The starting index of array1

0..(length of array1)-1	Valid
<0	The starting index would be 0
>=(length of array1)	The starting index would be the length of array2 (For index over the length of array2, an empty value would be captured)

int The number of element in array1 to be concatenated

0.. (length of array1)	Valid
<0	Invalid，length of array1 will be applied instead
>(length of array1)	Invalid，length of array1 will be applied instead

If the total number of starting index and assigning elements exceeds the length of array1, the surplus index will be suspended.

byte[] The input byte array2，would be concatenated after the end of array1

int The starting index of array2

0.. (length of array2)-1	Valid
<0	The starting index would be 0
>=(length of array2)	The starting index would be the length of array2 (For index over the length of array2, an empty value would be captured)

int The number of element in array2 to be concatenated
0.. (length of array2) Valid
<0 Invalid. Length of array2 will be applied instead.
>(length of array2) Invalid. Length of array2 will be applied instead.
If the total number of starting index and assigning elements exceeds the length of array2, the surplus index will be suspended.

Return

byte[] Byte array formed from concatenating input arrays.

Note

```
byte[] bb1 = {0x31, 0x32, 0x33, 0x00, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03}

value = Byte_Concat(bb1, 1, 3, bb2, 1, 2)    // value = {0x32, 0x33, 0x00, 0x02, 0x03}
value = Byte_Concat(bb1, -1, 3, bb2, 3, -1)  // value = {0x31, 0x32, 0x33}
```

Syntax 5

```
byte[] Byte_Concat(
    byte or byte[],
    byte or byte[],
    ...
)
```

Parameters *(active parameter amount)*

byte The input byte value
byte[] The input byte array
It concatenates the content of each parameter in order. It ignores the parameter if it is not a byte or a byte array and continues to concatenate the next parameter.

Return

byte[] Concatenate the parameters in byte and return a new byte array.

Note

```
byte[] bb1 = {0x31, 0x32, 0x00, 0x4F, 1}
byte[] bb2 = {0x01, 0x02, 0x03}
byte bb3 = 0x5A

value = Byte_Concat(bb1, bb2, bb3)
// value = {0x31,0x32,0x00,0x4F,0x01,0x01,0x02,0x03}   // Syntax 3
value = Byte_Concat(bb1, bb2, "", bb3)
// value = {0x31,0x32,0x00,0x4F,0x01,0x01,0x02,0x03,0x5A}
value = Byte_Concat(bb2, 0x10, bb1)
// value = {0x01,0x02,0x03,0x10,0x31,0x32,0x00,0x4F,0x01}
value = Byte_Concat(bb1, "AB", bb2, 10)
// value = {0x31,0x32,0x00,0x4F,0x01,0x01,0x02,0x03,0x0A}
// Parameter "AB" is the string type. Ignored.
value = Byte_Concat(bb1, "AB", bb2, 1000) // value =
{0x31,0x32,0x00,0x4F,0x01,0x01,0x02,0x03}
                                          // Parameter "AB" is the string type. Ignored.
                                          // Parameter 1000 is the integer type. Ignored.
```

4.11 String_ToInteger()

Transform string to integer (int type)

Syntax 1

int **String_ToInteger**(
string,
int
)

Parameters

string The input string.

int The input string's notation is decimal, hexadecimal or binary

10 decimal or auto format detecting (Default)

16 hexadecimal

2 binary

String's notation

123 decimal

0x7F hexadecimal

0b101 binary

Return

int The integer value formed from input string. If notation is invalid, returns 0.

Note

```
value = String_ToInteger("1234", 10)          // value = 1234
value = String_ToInteger("1234", 16)          // value = 4660
value = String_ToInteger("1234", 2)           // value = 0       // Invalid binary format
value = String_ToInteger("1100", 2)           // value = 12
value = String_ToInteger("0x1234", 10)        // value = 4660
                                              // Hexadecimal format by auto detecting
value = String_ToInteger("0x1234", 16)        // value = 4660
value = String_ToInteger("0x1234", 2)         // value = 0       // Invalid binary format
value = String_ToInteger("0b1100", 10)        // value = 12      // Binary format by auto detecting
value = String_ToInteger("0b1100", 16)        // value = 725248      // Valid Hexadecimal number
value = String_ToInteger("0b1100", 2)         // value = 12
value = String_ToInteger("+1234", 10)         // value = 1234
value = String_ToInteger("-1234", 10)         // value = -1234
value = String_ToInteger("-0x1234", 16)       // value = 0           // Invalid hex format
value = String_ToInteger("-0b1100", 2) /      / value = 0       // Invalid binary format
```

Syntax 2

int **String_ToInteger**(
string
)

Note

Similar to syntax1 with decimal format or auto format detection

String_ToInteger(str) => **String_ToInteger**(str, 10)

Syntax 3

int[] **String_ToInteger**(

string[],
int
)

Parameters

string[] Input string array

int The notation of element in input string array is decimal, hexadecimal or binary

10 decimal or auto format detecting (Default)

16 hexadecimal

2 binary

String's notation

123 decimal

0x7F hexadecimal

0b101 binary

* The notations of all the elements in a single array have to be identical

Return

int[] The integer array formed from input string array. If notation is invalid, returns 0.

Note

```
ss = {"12", "ab", "cc", "dd", "10"}
value = String_ToInteger(ss)        // value = {12, 0, 0, 0, 10}
                                    // "ab","cc","dd" are invalid decimal numbers
value = String_ToInteger(ss, 2)     // value = {0, 0, 0, 0, 2}
                                    // "12","ab","cc","dd" are invalid binary numbers
value = String_ToInteger(ss, 16)    // value = {18, 171, 204, 221, 16}
value = String_ToInteger(ss, 10)    // value = {12, 0, 0, 0, 10} // "ab","cc","dd" are invalid decimal
                                    numbers
```

4.12 String_ToFloat()

Transform string to floating-point (floating-point type)

Syntax 1

```
float String_ToFloat(
    string,
    int
)
```

Parameters

string	Input string	
int	Input string's notation is decimal, hexadecimal or binary format	
	10	decimal or auto format detecting (Default)
	16	hexadecimal
	2	binary
	String's notation	
	123	decimal
	0x7F	hexadecimal
	0b101	binary

Return

float The floating-point number formed from input string. If notation is invalid, returns 0.

Note

```
value = String_ToFloat("12.34", 10)     // value = 12.34
value = String_ToFloat("12.34", 16)     // value = 0          // Invalid hexadecimal format
value = String_ToFloat("12.34", 2)      // value = 0          // Invalid binary format
value = String_ToFloat("11.00", 2)      // value = 0          // Invalid binary format
value = String_ToFloat("0x1234", 10)    // value = 6.53E-42
                                        // Hexadecimal format by auto detecting
value = String_ToFloat("0x1234", 16)    // value = 6.53E-42
value = String_ToFloat("0x1234", 2)     // value = 0          // Invalid binary format
value = String_ToFloat("0b1100", 10)    // value = 1.7E-44    // Binary format by auto detecting
value = String_ToFloat("0b1100", 16)    // value = 1.016289E-39   // Valid hexadecimal format
value = String_ToFloat("0b1100", 2)     // value = 1.7E-44
value = String_ToFloat("+12.34", 10)    // value = 12.34
value = String_ToFloat("-12.34", 10)    // value = -12.34
value = String_ToFloat("-0x1234", 16)   // value = 0      // Invalid hex format
value = String_ToFloat("-0b1100", 2)    // value = 0      // Invalid format
```

Syntax 2

```
float String_ToFloat(
    string
)
```

Note

Similar to syntax1 with decimal format or auto format detection

String_ToFloat(str) => **String_ToFloat**(str, 10)

Syntax 3

```
float[] String_ToFloat(
```

string[],
int
)

Parameters

string[] Input string array

int The notation of elements in input string array is decimal, hexadecimal or binary

10 decimal or auto format detecting (Default)

16 hexadecimal

2 binary

String's notation

123 decimal

0x7F hexadecimal

0b101 binary

* The notation of all the elements in a single array have to be identical

Return

float[] The floating-point number array formed from input string array. If notation is invalid, returns 0.

Note

```
ss = {"12.345", "ab", "cc", "dd", "10.111"}
value = String_ToFloat(ss)          // value = {12.345,0,0,0,10.111}
value = String_ToFloat(ss, 2)       // value = {0,0,0,0,0}
value = String_ToFloat(ss, 16)      // value = {0,2.4E-43,2.86E-43,3.1E-43,0}
value = String_ToFloat(ss, 10)      // value = {12.345,0,0,0,10.111}
```

4.13 String_ToDouble()

Transform string to floating-point number (double type)

Syntax 1

double **String_ToDouble**(
string,
int
)

Parameters

string Input string

int Input string's notation is decimal, hexadecimal or binary format
10 decimal or auto format detecting (Default)
16 hexadecimal
2 binary
String's notation
123 decimal
0x7F hexadecimal
0b101 binary

Return

double The floating-point number formed from input string. If notation is invalid, returns 0.

Note

```
value = String_ToDouble("12.34", 10)   // value = 12.34
value = String_ToDouble("12.34", 16)   // value = 0          // Invalid hexadecimal format
value = String_ToDouble("12.34", 2)    // value = 0          // Invalid binary format
value = String_ToDouble("11.00", 2)    // value = 0          // Invalid binary format
value = String_ToDouble("0x1234", 10)  // value = 2.3023E-320    // Hexadecimal format by auto
                                          detecting
value = String_ToDouble("0x1234", 16)  // value = 2.3023E-320
value = String_ToDouble("0x1234", 2)   // value = 0              // Invalid binary format
value = String_ToDouble("0b1100", 10)  // value = 6E-323     // Binary format by auto detecting
value = String_ToDouble("0b1100", 16)  // value = 3.5832E-318    // Valid hexadecimal format
value = String_ToDouble("0b1100", 2)   // value = 6E-323
value = String_ToDouble("+12.34", 10)  // value = 12.34
value = String_ToDouble("-12.34", 10)  // value = -12.34
value = String_ToDouble("-0x1234", 16) // value = 0          // Invalid hex format
value = String_ToDouble("-0b1100", 2)  // value = 0      // Invalid binary format
```

Syntax 2

double **String_ToDouble**(
string
)

Note

Similar to syntax1 with decimal format or auto format detection
String_ToDouble(str) => **String_ToDouble**(str, 10)

Syntax 3

```
double[] String_ToDouble(
    string[],
    int
)
```

Parameters

`string[]` Input string array

`int` The notation of elements in input string array is decimal, hexadecimal or binary

- `10` decimal or auto format detecting (Default)
- `16` hexadecimal
- `2` binary

String's notation

- 123 decimal
- 0x7F hexadecimal
- 0b101 binary

* The notation of all the elements in a single array has to be identical

Return

`double[]` The floating-point number array formed from input string array. If notation is invalid, returns 0.

Note

```
ss = {"12.345", "ab", "cc", "dd", "10.111"}
value = String_ToDouble(ss)      // value = {12.345, 0, 0, 0, 10.111}
value = String_ToDouble(ss, 2)   // value = {0, 0, 0, 0, 0}
value = String_ToDouble(ss, 16)  // value = {0,8.45E-322,1.01E-321,1.09E-321,0}
value = String_ToDouble(ss, 10)  // value = {12.345, 0, 0, 0, 10.111}
```

4.14 String_ToByte()

Transform string to byte array

Syntax 1

```
byte[] String_ToByte(
    string,
    int
)
```

Parameters

string	Input string
int	The character encoding rules applied to input string
0	UTF8 (Default)
1	HEX BINARY // Stop at invalid Hex value
2	ASCII

Return

byte[]	The byte array formed from input string

Note

```
value = String_ToByte("12345", 0)       // value = {0x31, 0x32, 0x33, 0x34, 0x35}
value = String_ToByte("12345", 1)       // value = {0x12, 0x34, 0x50}      // the insufficient part will be filled with 0
value = String_ToByte("12345", 2)       // value = {0x31, 0x32, 0x33, 0x34, 0x35}
value = String_ToByte("0x12345", 0)     // value = {0x30, 0x78, 0x31, 0x32, 0x33, 0x34, 0x35}
value = String_ToByte("0x12345", 1)     // value = {0x00}        // Only 0 be transformed, cause x is an invalid Hex value
value = String_ToByte("0x12345", 2)     // value = {0x30, 0x78, 0x31, 0x32, 0x33, 0x34, 0x35}
value = String_ToByte("TM5機器人", 0)// value = {0x54, 0x4D, 0x35, 0xE6, 0xA9, 0x9F, 0xE5, 0x99, 0xA8, 0xE4, 0xBA, 0xBA}
value = String_ToByte("TM5機器人", 1) // value = {0x00}        // T is an invalid Hex value
value = String_ToByte("TM5機器人", 2) // value = {0x54, 0x4D, 0x35, 0x3F, 0x3F, 0x3F}
value = String_ToByte("0123456", 1)     // value = {0x01, 0x23, 0x45, 0x60}
value = String_ToByte("01234G5", 1) // value = {0x01, 0x23, 0x40} // G is an invalid Hex value
```

Syntax 2

```
byte[] String_ToByte(
    string
)
```

Note

Similar to syntax1 with UTF8 format

String_ToByte(str) => **String_ToByte**(str, 0)

4.15 String_IndexOf()

Search the address of the first occurrence of a specified strin from left to right.

Syntax 1

int **String_IndexOf**(
    string,
    string,
    int
)

Parameters

string	Input string
string	The specified string to search
int	The initial address to start searching

Return

int	0..(Length of string)-1	If the specified string is found, returns the index number
	-1	Not found
	0	The specified string is "" or empty

Syntax 2

int **String_IndexOf**(
    string,
    string
)

Note

Same as syntax 1. It defaults 0 to the initial address of the parameter int as searching from the leftmost.

```
int index = String_IndexOf("012314", "1")     // 1
index = String_IndexOf("012314", "")          // 0
index = String_IndexOf("012314", empty)       // 0
index = String_IndexOf("012314", "d")         // -1
index = String_IndexOf("", "d")               // -1
index = String_IndexOf("012314", "1", 1)      // 1   // Start searching with the 1st index number
index = String_IndexOf("012314", "1", 2)      // 4   // Start searching with the 2nd index number
index = String_IndexOf("012314", "1", 10)     // -1
```

Syntax 3

int **String_IndexOf**(
    string[],
    string,
    int
)

Parameters

string	The array of the input string
string	The specified string to search
int	The initial index of the array to start searching

Return

int	0..Array Size -1	Return the index of the string array if found the string.
	-1	Not found

* The array index will start searching with the initial index from left to right.
* Will use String_IndexOf(string, string) to search if the array element available.

Return the index number of the array element but not the index number of the string.

Syntax 4

```
int String_IndexOf(
    string[],
    string
)
```

Note

Same as syntax 3. It defaults 0 to the initial index of the parameter int as searching from the foremost of the array elements.

```
string[] ss = {"012314", "ABCDEF", "123TM"}
int index = String_IndexOf(ss, "1")  // 0
index = String_IndexOf(ss, "") // 0   // Since using String_IndexOf to search strings, it is available
                                       when searching for "".
index = String_IndexOf(ss, "d")      // -1
index = String_IndexOf(ss, "1", 1)  // 2
index = String_IndexOf(ss, "1", 10)// -1
```

4.16 String_LastIndexOf()

Search the address of the last occurrence of a specified strin from right to left.

Syntax 1

int **String_LastIndexOf**(
    string,
    string,
    int
)

Parameters

string	Input string	
string	The specified string to search	
int	The initial address to start searching	

Return

int	0..(Length of string)-1	If the specified string is found, returns the index number
	-1	Not found
	(Length of string)	The specified string is "" or empty

Syntax 2

int **String_LastIndexOf**(
    string,
    string
)

Note

Same as syntax 1. It defaults 0 to the initial address of the parameter int as searching from the rightmost.

```
int index = String_LastIndexOf("012314", "1")     // 4
index = String_LastIndexOf("012314", "")          // 6
index = String_LastIndexOf("012314", empty)       // 6
index = String_LastIndexOf("012314", "d")         // -1
index = String_LastIndexOf("", "d")               // -1
index = String_LastIndexOf("012314", "1", 1)      // 1
                                                  // Start searching with the 1st index number
index = String_LastIndexOf("012314", "1", 2)      // 1
                                                  // Start searching with the 2nd index number
index = String_LastIndexOf("012314", "1", 10)     // 4
index = String_LastIndexOf("012314", "4", 10)     // 5
```

Syntax 3

int **String_LastIndexOf**(
    string[],
    string,
    int
)

Parameters

string	The array of the input string

string	The specified string to search	
int	The initial index of the array to start searching	

Return

int	0..Array Size -1	Return the index of the string array if found the string.
	-1	Not found

* The array index will start searching with the initial index from right to left.
* Will use String_IndexOf(string, string) to search if the array element available. Return the index number of the array element but not the index number of the string.

Syntax 4

```
int String_LastIndexOf(
    string[],
    string
)
```

Note

Same as syntax 3. It defaults 0 to the initial index of the parameter int as the array size as searching from the last of the array elements.

```
string[] ss = {"012314", "ABCDEF", "123TM"}
int index = String_LastIndexOf(ss, "1") // 2
index = String_LastIndexOf(ss, "")      // 2   // Since using String_IndexOf to search strings, it is available when searching for "".
index = String_LastIndexOf(ss, "d")     // -1
index = String_LastIndexOf(ss, "1", 1)  // 0
index = String_LastIndexOf(ss, "1", 10)// 2
```

4.17 String_DiffIndexOf()

Compare the address where the first string difference occurs starting from the start address.

Syntax 1

int **String_DiffIndexOf**(
    string,
    string,
    int
)

Parameters

string	Input string 1	
string	Input string 2	
int	The initial address to start comparing	

Return

int	0..(Length of string)-1	If a difference is found, returns the index number of the difference.
	-1	No difference found. Namely, both strings match.
	-2	The initial address exceeds the length of two stings.

Syntax 2

int **String_DiffIndexOf**(
    string,
    string
)

Note

Same as syntax 1. It defaults 0 to the initial address of the parameter int as searching from the leftmost.

```
string s1 = "abcdef"
string s2 = "abcDef"
string s3 = "abcdeF123"
int index = String_DiffIndexOf(s1, s2)          // 3
index = String_DiffIndexOf(s1, s3)              // 5
index = String_DiffIndexOf(s1, s3, 5)           // 5   // Start comparing with index 5, f and F.
index = String_DiffIndexOf(s1, s3, 7)           // 7   // Start comparing with index 7, '\0' and 2.
index = String_DiffIndexOf(s1, "abcdef", 7)     // -1  // Both strings match.
index = String_DiffIndexOf(s1, "ABCDEF", 7)// -2// Start comparing with index 7. Exceeded the
                                                   length of two strings.
```

4.18 String_Substring()

Retrieve a substring from input string

Syntax 1

```
string String_Substring(
    string,
    int,
    int
)
```

Parameters

string	Input string
int	The starting character position of sub string (0 .. (length of input string)-1)
int	The length of substring

Return

string	Substring If starting character position <0, returns empty string If starting character position >= length of input string, returns empty string If length of substring <0, the substring ends at the last character of the input string If the sum of starting character position and length of substring exceeds the length of input string, the substring ends at the last character of the input string

Note

```
value = String_Substring("0x12345", 2, 4)       // value = "1234"
value = String_Substring("0x12345", -1, 4)      // value = ""
value = String_Substring("0x12345", 7, 4)       // value = ""
value = String_Substring("0x12345", 2, -1)      // value = "12345"
value = String_Substring("0x12345", 2, 100)     // value = "12345"
```

Syntax 2

```
string String_Substring(
    string,
    int
)
```

Note

Similar to syntax1 with the substring ends at the last character of the input string

String_Substring(str, 2) => **String_Substring**(str, 2, maxlen)

Syntax 3

```
string String_Substring(
    string,
    string,
    int
)
```

Parameters

string	Input string
string	The target string to be searched, the substring will start at its position, if it is

found

int The length of substring

Return

string Substring

If the target string is empty, the substring start at index zero

If the target string is not found, returns empty string

If length of substring <0, the substring ends at the last character of the input string

If the sum of starting character position and length of substring exceeds the length of input string, the substring ends at the last character of the input string

Note

This syntax is the same as **String_Substring**(str, **String_IndexOf**(str1), int)

```
value = String_Substring("0x12345", "1", 4)      // value = "1234"
value = String_Substring("0x12345", "", 4)       // value = "0x12"
value = String_Substring("0x12345", "7", 4)      // value = ""
value = String_Substring("0x12345", "1", -1)     // value = "12345"
value = String_Substring("0x12345", "1", 100)    // value = "12345"
```

Syntax 4

```
string String_Substring(
    string,
    string
)
```

Note

Similar to Syntax 3 with the substring ends at the last character of the input string

String_Substring(str, "1") => **String_Substring**(str, "1", maxlen)

Syntax 5

```
string String_Substring(
    string,
    string,
    string,
    int
)
```

Parameters

string Input string

string Prefix. The leading element of the substring

string Suffix. The trailing element of the substring

int The number of occurrence

Return

string Substring

If prefix and suffix are empty string, returns input string

If the number of occurrence<=0, returns empty string

Note

```
value = String_Substring("0x12345", "", "", 0)       // value = "0x12345"
value = String_Substring("0x12345", "1", "4", 1)     // value = "1234"
value = String_Substring("0x12345", "1", "4", 2)     // value = ""
value = String_Substring("0x12345", "1", "4", 0)     // value = ""
```

```
value = String_Substring("0x123450x12-345", "1", "4", 1) // value = "1234"
value = String_Substring("0x123450x12-345", "1", "4", 2) // value = "12-34"
value = String_Substring("0x123450x12-345", "1", "4", 3) // value = ""
value = String_Substring("0x12345122", "1", "", 1)     // value = "12345122"// Retrieves what's after the matched prefix
value = String_Substring("0x12345122", "1", "", 2)     // value = "122"  // Retrieves what's after the matched prefix. The matched amount moves from the front to the back.
value = String_Substring("0x12345122", "1", "", 4)     // value = ""
value = String_Substring("0x12345433", "", "4", 1)     // value = "0x123454"// Retrieves what's after the matched suffix
value = String_Substring("0x12345433", "", "4", 2)     // value = "0x1234"     // Retrieves what's after the matched suffix. The matched amount moves from the back to the front.
```

Syntax 6

```
string String_Substring(
    string,
    string,
    string
)
```

Note

Similar to Syntax 5 with the substring start at the first occurrence

String_Substring(str, prefix, suffix) => **String_Substring**(str, prefix, suffix, 1)

4.19 String_Split()

Split the string using specified separator.

Syntax 1

string[] **String_Split**(
    string,
    string,
    int
)

Parameters

string	Input string	
string	Separator (String)	
int	Format	
	0	Split and keep the empty strings
	1	Split and eliminate the empty strings
	2	Split with the elements inside double quotation mark skipped, and keep the empty strings
	3	Split with the elements inside double quotation mark skipped, and eliminate the empty strings

Return

string[]	Split substring If input string is empty, it returns a substring with array. [0] = empty and deals with empty strings by separators. If separator is empty, it returns substring with array [0] = Input string and deals with empty strings by separators.

Note

```
value = String_Split("0x112345", "1", 0)      // value = {"0x","","2345"}
value = String_Split("0x112345", "1", 1)      // value = {"0x","2345"}
value = String_Split("", "1", 0)              // value = {""}     // length = 1
value = String_Split("", "1", 1)              // value = {}             // length = 0
value = String_Split("0x112345", "", 0)       // value = {"0x112345"}

s1 = "123, ""456,67"",89"
value = String_Split(s1, ",", 0)          // value = {"123", """456", "67""", "89"} // length = 4
value = String_Split(s1, ",", 2)          // value = {"123", """456,67""", "89"}    // length = 3
```

Syntax 2

string[] **String_Split**(
    string,
    string
)

Note

Similar to Syntax1 with splitting and keeping the empty strings
String_Split(str, separator) => **String_Split**(str, separator, 0)

4.20 String_Replace()

Return a new string in which all occurrences of a specified string in the input string are replaced with another specified string

Syntax 1

```
string String_Replace(
    string,
    string,
    string
)
```

Parameters

string	Input string
string	Old value, the string to be replaced
string	New value, the string to replace all occurrences of old value

Return

string	The string formed by replacing the old value with new value in input value. If the old value is empty, returns the input string

Note

```
value = String_Replace("0x112345", "1", "2")    // value = "0x222345"
value = String_Replace("0x112345", "", "2")     // value = "0x112345"
value = String_Replace("0x112345", "1", "")     // value = "0x2345"
```

4.21 String_Trim()

Return a new string in which all leading and trailing occurrences of specified characters or white-space characters from the input string are removed

Syntax 1

string **String_Trim**(
    string
)

Parameters

    string   Input string

Return

    string   String formed by removing all leading and trailing occurrences of white-space characters

Note

```
value = String_Trim("0x112345 ")        // value = "0x112345"
value = String_Trim(" 0x112345")        // value = "0x112345"
value = String_Trim(" 0x112345    ")    // value = "0x112345"
```

White-space characters

\u0020	\u1680	\u2000	\u2001	\u2002	\u2003	\u2004
\u2005	\u2006	\u2007	\u2008	\u2009	\u200A	\u202F
\u205F	\u3000					
\u2028						
\u2029						
\u0009	\u000A	\u000B	\u000C	\u000D	\u0085	\u00A0
\u200B	\uFEFF					

Syntax 2

string **String_Trim**(
    string,
    string
)

Parameters

    string   Input string
    string   Specified characters to be removed from leading occurrences

Return

    string   String formed by removing all leading occurrences of specified characters

Syntax 3

string **String_Trim**(
    string,
    string,
    string
)

Parameters

    string   Input string
    string   Specified characters to be removed from leading occurrences

string Specified characters to be removed from trailing occurrences

Return

string String formed by removing all leading and trailing occurrences of the specified characters

Note

```
string s1 = "Hello  Hello  World  Hello  World"
string s2 = "HelloHelloWorldHelloWorld"
value = String_Trim(s1, "Hello")              // value = "  Hello  World  Hello  World"
value = String_Trim(s1, "World")              // value = "Hello  Hello  World  Hello  World"
value = String_Trim(s1, "", "Hello")          // value = "Hello  Hello  World  Hello  World"
value = String_Trim(s1, "", "World")          // value = "Hello  Hello  World  Hello  "
value = String_Trim(s1, "Hello", "World")     // value = "  Hello  World  Hello  "
value = String_Trim(s2, "Hello")              // value = "WorldHelloWorld"
value = String_Trim(s2, "World")              // value = "HelloHelloWorldHelloWorld"
value = String_Trim(s2, "", "Hello")          // value = "HelloHelloWorldHelloWorld"
value = String_Trim(s2, "", "World")          // value = "HelloHelloWorldHello"
value = String_Trim(s2, "Hello", "World")     // value = "WorldHello"
```

4.22 String_ToLower()

Change all the characters in a string to lower case

Syntax 1

string **String_ToLower**(
    string
)

Parameters

string	Input string

Return

string	The string formed by converting all the English character into lower case. Non-English character will be remained the same.

Note

```
value = String_ToLower("0x11Acz34")  // value = "0x11acz34"
```

4.23 String_ToUpper()

Change all the characters in a string to upper case

Syntax 1

string **String_ToUpper**(
    string
)

Parameters

string	Input string

Return

string	The string formed by converting all the English character into upper case. Non-English character will remain the same.

Note

```
value = String_ToUpper("0x11Acz34")  // value = "0X11ACZ34"
```

4.24 Array_Append()

Add new data as the elements in the end of the array.

Syntax 1

```
?[] Array_Append(
    ?[],
    ? or ?[]
)
```

Parameters

?[]	Parameter 1, the array to be appended. Available types: byte, int, float, double, bool, and string.
? or ?[]	Parameter 2, the data or the array to add. The type must be the same with the type of the array to be appended. *Both parameters must go with the same type.

Return

?[]	The new array with the parameter 2 elements appended to the parameter 1.

Note

```
? byte[] n1 = {100, 200, 30}
  byte[] n2 = {40, 50, 60}
  n3 = Array_Append(n1, n2)          // n3 = {100, 200, 30, 40, 50, 60}
  n1 = Array_Append(n1, 100)         // n1 = {100, 200, 30, 100}
  n1 = Array_Append(n1, n3)          // n1 = {100, 200, 30, 100, 100, 200, 30, 40, 50, 60}

? float[] n1 = {1.1, 2.2, 3.3}
  float[] n2 = {0.4, 0.5}
  n3 = Array_Append(n1, n2)          // n3 = {1.1, 2.2, 3.3, 0.4, 0.5}
  n4 = Array_Append(n3, 5.678)       // n4 = {1.1, 2.2, 3.3, 0.4, 0.5, 5.678}

? string[] n1 = {"123", "ABC", "456", "DEF"}
  string[] n2 = {"ABC", "123", "XYZ"}
  n3 = Array_Append(n1, n2)          // n3 = {"123", "ABC", "456", "DEF", "ABC", "123", "XYZ"}
  n4 = Array_Append(n2, "Hello World") // n4 = {"ABC", "123", "XYZ", "Hello World"}
```

4.25 Array_Insert()

Insert data as the elements in the array.

Syntax1

?[] **Array_Insert**(
    ?[],
    int,
    ? or ?[]
)

Parameters

?[]	Parameter 1, the array to be inserted. Available types: byte, int, float, double, bool, and string.	
int	The index starting address of the parameter 1.	
	0	Legal value
	The length of the array 1 - 1	
	>= The length of the array 1	Legal value, and will insert the value in the end of the parameter 1.
	< 0	Illegal value, the project will stop by error.
? or ?[]	Parameter 2, the data or the array to insert. The type must be the same with the type of the array to be appended. * Both parameters must go with the same type.	

Return

?[]	The new array with the parameter 2 elements inserted to the index starting address of the parameter 1.

Note

```
?   int[] n1 = {100, 200, 30}
    int[] n2 = {40, 50, 60}
    n3 = Array_Insert(n1, 0, n2)    // n3 = {40, 50, 60, 100, 200, 30}// Insert to the index 0
    n4 = Array_Insert(n1, 2, n2)    // n4 = {100, 200, 40, 50, 60, 30}// Insert to the index 2
    n5 = Array_Insert(n1, -1, n2)   // n5 = {}
                                    // The project will stop by error. Illegal index to start with

?   double[] n1 = {1.4, 2.6, 3.9}
    double[] n2 = {0.5, 0.7}
    n3 = Array_Insert(n1, 1, n2)        // n3 = {1.4, 0.5, 0.7, 2.6, 3.9}
    n4 = Array_Insert(n3, 4, 1.2345)    // n4 = {1.4, 0.5, 0.7, 2.6, 1.2345, 3.9}
    n5 = Array_Insert(n3, 100, 9)       // n5 = {1.4, 0.5, 0.7, 2.6, 3.9, 9}
                                        // Out of the index. The value will insert in the end of the array.
```

4.26 Array_Remove()

Delete data as the elements in the array.

Syntax1

```
?[] Array_Remove(
    ?[],
    int,
    int
)
```

Parameters

?[]	Parameter 1, the array to be inserted. Available types: byte, int, float, double, bool, and string.	
int	The index starting address of the parameter 1 to remove.	
	0	Legal value
	The length of the parameter 1 - 1	
	>= The length of the parameter 1	Illegal value, the project will stop by error.
	< 0	Illegal value, the project will stop by error.
int	The number of the elements to remove	
	> 0	The number of the elements to remove from the index starting address or until the end of the array.
	< 0	The number will be 0 and no element will be removed.

Return

?[]	The new array with elements removed after the index staring address.

Syntax2

```
?[] Array_Remove(
    ?[],
    int
)
```

Note

Same as syntax 1. The default number of the elements to remove is 1.

```
? int[] n1 = {100, 200, 30, 40, 50, 60}
    n3 = Array_Remove(n1, -1)     // n3 = {}
                                  // The project will stop by error. Illegal value to start with.
    n4 = Array_Remove(n1, 100)    // n4 = {}
                                  // The project will stop by error. Illegal value to start with.
    n5 = Array_Remove(n1, 0)      // n5 = {200, 30, 40, 50, 60}      // Remove index 0
    n6 = Array_Remove(n1, 1, 2)   // n6 = {100, 40, 50, 60}     // Remove 2 elements from index 1
    n7 = Array_Remove(n1, 1, 100)     // n7 = {100}     // Remove 100 elements from index 1 (remove
                                      to the end of the array)
    n8 = Array_Remove(n1, Length(n1)-1) // n8 = {100,200,30,40,50,60}
                                        // Remove from the last of index
    n9 = Array_Remove(n1, Length(n1))   // n9 = {}
                                        // The project will stop by error. Illegal value to start with.
```

4.27 Array_Equals()

Determine whether the specified two arrays are identical.

Syntax 1

```
bool Array_Equals(
    ?[],
    ?[]
)
```

Parameters

?[]	Input array1 (Data type can be byte, int, float, double, bool, string)
?[]	Input array2 (Data type can be byte, int, float, double, bool, string)
	* The data type of array1 and array2 must be identical.

Return

bool Two arrays are identical or not?

true	two arrays are identical
false	two arrays are not identical

Syntax 2

```
bool Array_Equals(
    ?[],vv
    int,
    ?[],
    int,
    int
)
```

Parameters

?[]	Input array1 (Data type can be byte, int, float, double, bool, string)
int	The starting index of array1 (0 .. (length of arry1)-1)
?[]	Input array2 (Data type can be byte, int, float, double, bool, string)
int	The starting index of array2 (0 .. (length of arry2)-1)
int	The number of elements to be compared (0: return true, <0: return false)
	* The data type of array1 and array2 must be identical.

Return

bool The assigned elements in two arrays are identical or not?

true	identical
false	not identical (or parameters are not valid)

Note

```
?   byte[] n1 = {100, 200, 30}
    byte[] n2 = {100, 200, 30}
    Array_Equals(n1, n2)                        // true
    Array_Equals(n1, 0, n2, 0, 3)               // true
    Array_Equals(n1, 0, n2, 0, Length(n2))      // true

?   int[] n1 = {1000, 2000, 3000}
    int[] n2 = {1000, 2000, 3000, 4000}
    Array_Equals(n1, n2)                        // false
    Array_Equals(n1, 0, n2, 0, Length(n2)) // false     // compare 4 elements
```

```
    Array_Equals(n1, 0, n2, 0, 3)                 // true
?   float[] n1 = {1.1, 2.2, 3.3}
    float[] n2 = {1.1, 2.2}
    Array_Equals(n1, n2)                          // false
    Array_Equals(n1, 0, n2, 0, Length(n2))        // true      // compare 2 elements
    Array_Equals(n1, 0, n2, 0, Length(n1))        // false
?   double[] n1 = {100, 200, 300, 3.3, 2.2, 1.1}
    double[] n2 = {100, 200, 400, 3.3, 2.2, 4.4}
    Array_Equals(n1, n2)                          // false
    Array_Equals(n1, 0, n2, 0, Length(n2))        // false
    Array_Equals(n1, 0, n2, 0, 2)                 // true
    Array_Equals(n1, 3, n2, 3, 2)                 // true
?   bool[] n1 = {true, false, true, true, true}
    bool[] n2 = {true, false, true, false, true}
    Array_Equals(n1, n2)                          // false
    Array_Equals(n1, 0, n2, 0, -1)                // false
    Array_Equals(n1, 0, n2, 0, 0)                 // true      // compare 0 element
?   string[] n1 = {"123", "ABC", "456", "DEF"}
    string[] n2 = {"123", "ABC", "456", "DEF"}
    Array_Equals(n1, n2)                          // true
    Array_Equals(n1, -1, n2, 0, 4)                // false     // Invalid starting index
```

4.28 Array_IndexOf()

Search for the index number of the first occurrence within array elements.

Syntax 1

```
int Array_IndexOf(
    ?[],
    ?,
    int
)
```

Parameters

?[]	input array (Data type can be byte, int, float, double, bool, string)
?	The target element to search (The data type needs to be the same as the input array ?[], but not an array.)
int	The initial index of the array to start searching

Return

int	0..(length of input array)-1	If the element is found , it returns the index number.
	-1	No element found

Syntax 2

```
int Array_IndexOf(
    ?[],
    ?
)
```

Note

Same as syntax 1. It defaults 0 to the initial address of the parameter int as searching from the foremost.

```
?   byte[] n = {100, 200, 30, 100}
    value = Array_IndexOf(n, 200)       // 1
    value = Array_IndexOf(n, 2000)      // -1 // Since 2000 is not a byte type, it will be converted to int[], int to search.
    value = Array_IndexOf(n, 100, 1)    // 3

?   int[] n = {1000, 2000, 3000, 1000}
    value = Array_IndexOf(n, 200)       // -1
    value = Array_IndexOf(n, 1000)      // 0
    value = Array_IndexOf(n, 1000, 1)   // 3

?   float[] n = {1.1, 2.2, 3.3, 1.1}
    value = Array_IndexOf(n, 1.1)       // 0
    value = Array_IndexOf(n, 4.4)       // -1
    value = Array_IndexOf(n, 1.1, 1)    // 3

?   double[] n = {100, 200, 300, 3.3, 2.2, 1.1, 100}
    value = Array_IndexOf(n, 1.1)       // 5
    value = Array_IndexOf(n, 500)       // -1
    value = Array_IndexOf(n, 100, 1)    // 6
```

```
?    bool[] n = {true, false, true, true, true}
     value = Array_IndexOf(n, true)// 0
     value = Array_IndexOf(n, false)      // 1
     value = Array_IndexOf(n, false, 2)  // -1
     value = Array_IndexOf(n, true, 2)   // 2

?    string[] n = {"123", "ABC", "456", "DEF", "123"}
     value = Array_IndexOf(n, "456")     // 2
     value = Array_IndexOf(n, "789")     // -1
     value = Array_IndexOf(n, "123", 1) // 4
     value = Array_IndexOf(n, "AB")      // -1
```

4.29 Array_LastIndexOf()

Search for the index number of the last occurrence within array elements.

Syntax 1

```
int Array_LastIndexOf(
    ?[],
    ?,
    int
)
```

Parameters

?[]	input array (Data type can be byte, int, float, double, bool, string)
?	The target element to search (The data type needs to be the same as the input array ?[], but not an array.)
int	The initial index of the array to start searching

Return

int	0..(length of input array)-1	If the element is found , returns the index value
	-1	No element found

Syntax 2

```
int Array_LastIndexOf(
    ?[],
    ?
)
```

Note

Same as syntax 1. It defaults 0 to the initial address of the parameter int as searching from the foremost.

```
?   byte[] n = {100, 200, 30}

?   byte[] n = {100, 200, 30, 100}
    value = Array_LastIndexOf(n, 200)      // 1
    value = Array_LastIndexOf(n, 2000)     // -1 // Since 2000 is not a byte type, it will be converted to
                                           int[], int to search.
    value = Array_LastIndexOf(n, 100, 1)   // 0

?   int[] n = {1000, 2000, 3000, 1000}
    value = Array_LastIndexOf(n, 200)      // -1
    value = Array_LastIndexOf(n, 1000)     // 3
    value = Array_LastIndexOf(n, 1000, 1)  // 0

?   float[] n = {1.1, 2.2, 3.3, 1.1}
    value = Array_LastIndexOf(n, 1.1)      // 3
    value = Array_LastIndexOf(n, 4.4)      // -1
    value = Array_LastIndexOf(n, 1.1, 1)   // 0

?   double[] n = {100, 200, 300, 3.3, 2.2, 1.1, 100}
    value = Array_LastIndexOf(n, 1.1)      // 5
    value = Array_LastIndexOf(n, 500)      // -1
    value = Array_LastIndexOf(n, 100, 1)   // 0
```

```
?    bool[] n = {true, false, true, true, true}
     value = Array_LastIndexOf(n, true)// 4
     value = Array_LastIndexOf(n, false)      // 1
     value = Array_LastIndexOf(n, false, 2)  // 1
     value = Array_LastIndexOf(n, true, 2)   // 2

?    string[] n = {"123", "ABC", "456", "DEF", "123"}
     value = Array_LastIndexOf(n, "456")     // 2
     value = Array_LastIndexOf(n, "789")     // -1
     value = Array_LastIndexOf(n, "123", 1) // 0
     value = Array_LastIndexOf(n, "AB")      // -1
```

4.30 Array_Reverse()

Reverse the sequence of the elements in the array

Syntax 1

?[] **Array_Reverse**(
    ?[]
)

Parameters

?[]	input array (Data type can be byte, int, float, double, bool, string)

Return

?[]	The reversed array

Note

```
?   byte[] n = {100, 200, 30}
    n = Array_Reverse(n)      // n = {30, 200, 100}
?   int[] n = {1000, 2000, 3000}
    n = Array_Reverse(n)      // n = {3000, 2000, 1000}
?   float[] n = {1.1, 2.2, 3.3}
    n = Array_Reverse(n)      // n = {3.3, 2.2, 1.1}
?   double[] n = {100, 200, 300, 3.3, 2.2, 1.1}
    n = Array_Reverse(n)      // n = {1.1, 2.2, 3.3, 300, 200, 100}
?   bool[] n = {true, false, true, true, true}
    n = Array_Reverse(n)      // n = {true, true, true, false, true}
?   string[] n = {"123", "ABC", "456", "DEF"}
    n = Array_Reverse(n)      // n = {"DEF", "456", "ABC", "123"}
```

Syntax 2

?[] **Array_Reverse**(
    ?[],
    int
)

Parameters

?[]	input array (Data type can be byte, int, float, double, bool, string)
int	the number of elements to be viewed as a section to be reversed
2	2 elements as a section
4	4 elements as a section
8	8 elements as a section

* The sequence of the elements in the same section will be reversed, but the sequence of the sections will remain the same

Return

?[]	The reversed array

Note

```
?   byte[] n = {100, 200, 30}
    n = Array_Reverse(n,   2) // n = {200, 100, 30}
                              // 2 elements as a section, that is {100,200}{30}
    n = Array_Reverse(n,   4) // n = {30, 200, 100}
                              // 4 elements as a section, that is {100,200,30}
    n = Array_Reverse(n,   8) // n = {30, 200, 100}
```

```
?   int[] n = {100, 200, 300, 400}
    n = Array_Reverse(n,   2) // n = {200, 100, 400, 300}
                              // 2 elements as a section, that is {100,200}{300,400}
    n = Array_Reverse(n,   4) // n = {400, 300, 200, 100}
                              // 4 elements as a section, that is {100,200,300,400}
    n = Array_Reverse(n,   8) // n = {400, 300, 200, 100}
?   float[] n = {1.1, 2.2, 3.3, 4.4, 5.5}
    n = Array_Reverse(n,   2) // n = {2.2, 1.1, 4.4, 3.3, 5.5}
                              // 2 elements as a section, that is {1.1,2.2}{3.3,4.4}{5.5}
    n = Array_Reverse(n,   4) // n = {4.4, 3.3, 2.2, 1.1, 5.5}
                              // 4 elements as a section, that is {1.1,2.2,3.3,4.4}{5.5}
    n = Array_Reverse(n,   8) // n = {5.5, 4.4, 3.3, 2.2, 1.1}
?   double[] n = {100, 200, 300, 400, 4.4, 3.3, 2.2, 1.1, 50, 60, 70, 80}
    n = Array_Reverse(n,   2) // n = {200, 100, 400, 300, 3.3, 4.4, 1.1, 2.2, 60, 50, 80, 70}
    n = Array_Reverse(n,   4) // n = {400, 300, 200, 100, 1.1, 2.2, 3.3, 4.4, 80, 70, 60, 50}
    n = Array_Reverse(n,   8) // n = {1.1, 2.2, 3.3, 4.4, 400, 300, 200, 100, 80, 70, 60, 50}
?   bool[] n = {true, false, true, true, true, false, true, false}
    n = Array_Reverse(n,   2) // n = {false, true, true, true, false, true, false, true }
    n = Array_Reverse(n,   4) // n = {true, true, false, true, false, true, false, true}
    n = Array_Reverse(n,   8) // n = {false, true, false, true, true, true, false, true}
?   string[] n = {"123", "ABC", "456", "DEF", "000", "111"}
    n = Array_Reverse(n,   2) // n = {"ABC", "123", "DEF", "456", "111", "000"}
    n = Array_Reverse(n,   4) // n = {"DEF", "456", "ABC", "123", "111", "000"}
    n = Array_Reverse(n,   8) // n = {"111", "000", "DEF", "456", "ABC", "123"}
```

4.31 Array_Sort()

Sort the elements in a array

Syntax 1

?[] **Array_Sort**(
    ?[],
    int
)

Parameters

?[]	input array (Data type can be byte, int, float, double, bool, string)
int	Sorting direction
0	Ascending Order (Default)
1	Descending Order

Return

?[]	The array after sorting

Syntax 2

?[] **Array_Sort**(
    ?[]
)

Note

Similar to Syntax1 with sorting direction as ascending order
Array_Sort(array[]) => **Array_Sort**(array[], 0)

```
? int[] n = {1000, 2000, 3000}
  n = Array_Sort(n )          // n = {1000, 2000, 3000}
? double[] n = {100, 200, 300, 3.3, 2.2, 1.1}
  n = Array_Sort(n , 1)       // n = {300, 200, 100, 3.3, 2.2, 1.1}
? bool[] n = {true, false, true, true, true}
  n = Array_Sort(n , 1)       // n = {true, true, true, true, false}
? string[] n = {"123", "ABC", "456", "DEF"}
  n = Array_Sort(n )          // n = {"123", "456", "ABC", "DEF"}
```

4.32 Array_SubElements()

Retrieve the sub-elements from input array

Syntax 1

?[] **Array_SubElements**(
    ?[],
    int,
    int
)

Parameters

?[]	Input array (Data type can be byte, int, float, double, bool, string)
int	The starting index of sub-elements. (0 .. (length of array)-1)
int	The number of element in sub-elements

Return

?[]	The sub-elements from input arrays If starting index <0, sub-elements equals empty array If starting index >= length of input array, sub-elements equals empty array If sub-element number <0, sub-elements starts at starting index to the last element of input array If the sum of starting index and the number of element exceeds the length of the input array, sub-elements starts at starting index to the last element of input array

Syntax 2

?[] **Array_SubElements**(
    ?[],
    int
)

Note

Similar to Syntax 1, but the sub-elements starts at starting index to the last element of input array

Array_SubElements(array[], 2) => **Array_SubElements**(array[], 2, maxlen)

```
?   byte[] n = {100, 200, 30}
    n1 =  Array_SubElements(n1 , 0)      // n1 =  {100, 200, 30}
    n1 =  Array_SubElements(n1 , -1)     // n1 =  {}
    n1 =  Array_SubElements(n1 , 0, 3)   // n1 =  {100, 200, 30}
    n1 =  Array_SubElements(n1 , 1, 3)   // n1 =  {200, 30}
    n1 =  Array_SubElements(n1 , 2)      // n1 =  {30}
    n1 =  Array_SubElements(n1 , 3, 3)   // n1 =  {}
?   int[] n =  {1000, 2000, 3000}
    n1 =  Array_SubElements(n1 , 0)      // n1 =  {1000, 2000, 3000}
    n1 =  Array_SubElements(n1 , -1)     // n1 =  {}
    n1 =  Array_SubElements(n1 , 1, 3)   // n1 =  {2000, 3000}
    n1 =  Array_SubElements(n1 , 2)      // n1 =  {3000}
?   float[] n =  {1.1, 2.2, 3.3}
    n1 =  Array_SubElements(n1 , 0)      // n1 =  {1.1, 2.2, 3.3}
    n1 =  Array_SubElements(n1 , -1)     // n1 =  {}
```

```
    n1 =   Array_SubElements(n1 , 1, 3)   // n1 =  {2.2, 3.3}
    n1 =   Array_SubElements(n1 , 2)      // n1 =  {3.3}
?   double[] n =   {100, 200, 3.3, 2.2, 1.1}
    n1 =   Array_SubElements(n1 , 0)      // n1 =  {100, 200, 3.3, 2.2, 1.1}
    n1 =   Array_SubElements(n1 , -1)     // n1 =  {}
    n1 =   Array_SubElements(n1 , 1, 3)   // n1 =  {200, 3.3, 2.2}
    n1 =   Array_SubElements(n1 , 2)      // n1 =  {3.3, 2.2, 1.1}
?   bool[] n =   {true, false, true, true, true}
    n1 =   Array_SubElements(n1 , 0)      // n1 =  {true, false, true, true, true}
    n1 =   Array_SubElements(n1 , -1)     // n1 =  {}
    n1 =   Array_SubElements(n1 , 1, 3)   // n1 =  {false, true, true}
    n1 =   Array_SubElements(n1 , 2)      // n1 =  {true, true, true}
?   string[] n =   {"123", "ABC", "456", "DEF"}
    n1 =   Array_SubElements(n1 , 0)      // n1 =  {"123", "ABC", "456", "DEF"}
    n1 =   Array_SubElements(n1 , -1)     // n1 =  {}
    n1 =   Array_SubElements(n1 , 1, 3)   // n1 =  {"ABC", "456", "DEF"}
    n1 =   Array_SubElements(n1 , 2)      // n1 =  {"456", "DEF"}
```

4.33 ValueReverse()

Reverse the sequence of byte units inside input data (int 2 bytes or 4 bytes, float 4 bytes, double 8 bytes); or reverse the sequence of character of string.

Syntax 1

int **ValueReverse**(
    int,
    int
)

Parameters

int	Input value
int	The input value follows int32 or int16 format
	0 int32 (Default)
	1 int16. If the data does not meets int16 format, int32 will be applied instead.
	2 int16. Forced to apply int16 format. For int32 data input, there could be some bytes missing

Return

int	The value formed from reversing the sequence of byte units inside the input value. For Int32 data, reverse with 4 bytes. For int16 data, reverse with 2 bytes.

Note

```
int i = 10000
value = ValueReverse(i, 0)    // 10000=0x00002710 → 0x10270000// value = 270991360
value = ValueReverse(i, 1)    // 10000=0x2710      → 0x1027      // value = 4135
i = 100000                    // int32 value
value = ValueReverse(i, 0)    // 100000=0x000186A0 → 0xA0860100 // value = -1601830656
value = ValueReverse(i, 1)    // 100000=0x000186A0 → 0xA0860100 // value = -1601830656
value = ValueReverse(i, 2)    // 100000=0x000086A0 → 0xA0860000 // value = -24442
```

Syntax 2

int **ValueReverse**(
    int
)

Parameters

int	Input value

Note

Similar to Syntax1 with int32 input format

ValueReverse(int) => **ValueReverse**(int, 0)

Syntax 3

float **ValueReverse**(
    float
)

Parameters

float	Input value

Return

float	The value formed from reversing the sequence of byte units inside the input value. For float data, reverse 4 bytes.

Note

float i = 40000

value = **ValueReverse**(i) // 40000=0x471C4000 → 0x00401C47 // value = 5.887616E-39

Syntax 4

double **ValueReverse**(

double

)

Parameters

double Input value

Return

double The value formed from reversing the sequence of byte units inside the input value. For double data, reverse 8 bytes.

Note

double i = 80000

value = **ValueReverse**(i) // 80000=0x40F3880000000000 → 0x000000000088F340

// value = 4.43432217445369E-317

Syntax 5

string **ValueReverse**(

string

)

Parameters

string Input string

Return

string The value formed from reversing the sequence of characters of input string.

Note

string i = "ABCDEF"

value = **ValueReverse**(i) // value = "FEDCBA"

Syntax 6

int[] **ValueReverse**(

int[],

int

)

Parameters

int[] Input array value

int The input value follows int32 or int16 format

0 int32 (Default)

1 int16. If the data does not meets int16 format, int32 will be applied instead.

2 int16. Forced to apply int16 format. For int32 data input, there could be some bytes missing

Return

int[] The array formed from reversing the sequence of byte units inside every element of the input array.

Note

int[] i = {10000, 20000, 60000, 80000}

value = **ValueReverse**(i, 0) // value = {270991360, 541982720, 1625948160, -2143813376}

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```
value = ValueReverse(i, 1)      // value = {4135, 8270, 1625948160, -2143813376}
value = ValueReverse(i, 2)      // value = {4135, 8270, 24810, -32712}
```

Syntax 7

int[] **ValueReverse**(
    int[]
)

Parameters

int[] Input array value

Note

Similar to Syntax6 with input integer as int32
ValueReverse(int[]) => **ValueReverse**(int[], 0)

Syntax 8

float[] **ValueReverse**(
    float[]
)

Parameters

float[] Input array value

Return

float[] The array formed from reversing the sequence of byte units inside every element of the input array.

Note

```
float[] i = {10000, 20000}
value = ValueReverse(i)   // value = {5.887614E-39, 5.933532E-39}
```

Syntax 9

double[] **ValueReverse**(
    double[]
)

Parameters

double[] Input array value

Return

double[] The array formed from reversing the sequence of byte units inside every element of the input array.

Note

```
double[] i = {10000, 20000}
value = ValueReverse(i)   // value = {4.428251E-317,4.430275E-317}
```

Syntax 10

string[] **ValueReverse**(
    string[]
)

Parameters

string[] Input string array

Return

string[] The string array formed from reversing the string inside every element of the input string array.

Note

```
string[] i = {"ABCDEFG", "12345678"}
value = ValueReverse(i)    // value = {"GFEDCBA", "87654321"}
```

4.34 GetBytes()

Convert arbitrary data type to byte array.

Syntax 1

byte[] **GetBytes**(
    ?,
    int
)

Parameters

?	The input data. Data type can be int, float, double, bool, string or array.	
int	The input data as integers and floating points follows Little Endian or Big Endian	
	0	Little Endian (Default)
	1	Big Endian
	The input data as string arrays separates with 0x00 0x00 for each element	
	0	Not separate with 0x00 0x00 (Default)
	1	Separate with 0x00 0x00

Return

byte[]	The byte array formed by input data

Syntax 2

byte[] **GetBytes**(
    ?
)

Note

Same as syntax 1 with Little Endian or Big Endian defaults to 0 such as returns based on Little Endian

GetBytes(?) => **GetBytes**(?, 0)

```
? byte n = 100
    value = GetBytes(n)         // value = {0x64}
    value = GetBytes(n, 0)      // value = {0x64}
    value = GetBytes(n, 1)      // value = {0x64}

? byte[] n = {100, 200}         // Convert every element of the array to byte, 1 byte as a single unit.
    value = GetBytes(n)         // value = {0x64, 0xC8}
    value = GetBytes(n, 0)      // value = {0x64, 0xC8}
    value = GetBytes(n, 1)      // value = {0x64, 0xC8}

? int
    value = GetBytes(123456)        // value = {0x40, 0xE2, 0x01, 0x00}
    value = GetBytes(123456, 0)     // value = {0x40, 0xE2, 0x01, 0x00}
    value = GetBytes(0x123456, 0)       // value = {0x56, 0x34, 0x12, 0x00}
    value = GetBytes(0x1234561, 1)      // value = {0x01, 0x23, 0x45, 0x61}

? int[] n = {10000, 20000, 80000}
    // Convert every single element of the array to byte. For int32 data, works on 4 bytes sequentially.
```

```
value = GetBytes(n)
// value = {0x10, 0x27, 0x00, 0x00, 0x20, 0x4E, 0x00, 0x00, 0x80, 0x38, 0x01, 0x00}
value = GetBytes(n, 0)
// value = {0x10, 0x27, 0x00, 0x00, 0x20, 0x4E, 0x00, 0x00, 0x80, 0x38, 0x01, 0x00}
value = GetBytes(n, 1)
// value = {0x00, 0x00, 0x27, 0x10, 0x00, 0x00, 0x4E, 0x20, 0x00, 0x01, 0x38, 0x80}
```

? float

```
value = GetBytes(123.456, 0)  // value = {0x79, 0xE9, 0xF6, 0x42}
float n = -1.2345
value = GetBytes(n, 0)        // value = {0x19, 0x04, 0x9E, 0xBF}
value = GetBytes(n, 1)        // value = {0xBF, 0x9E, 0x04, 0x19}
```

? float[] n = {1.23, 4.56, -7.89}

```
// Convert every single element of the array to byte. For float data, works on 4 bytes sequentially.
value = GetBytes(n)
// value = {0xA4, 0x70, 0x9D, 0x3F, 0x85, 0xEB, 0x91, 0x40, 0xE1, 0x7A, 0xFC, 0xC0}
value = GetBytes(n, 0)
// value = {0xA4, 0x70, 0x9D, 0x3F, 0x85, 0xEB, 0x91, 0x40, 0xE1, 0x7A, 0xFC, 0xC0}
value = GetBytes(n, 1)
// value = {0x3F, 0x9D, 0x70, 0xA4, 0x40, 0x91, 0xEB, 0x85, 0xC0, 0xFC, 0x7A, 0xE1}
```

? double n = -1.2345

```
value = GetBytes(n, 0)    // value = {0x8D, 0x97, 0x6E, 0x12, 0x83, 0xC0, 0xF3, 0xBF}
value = GetBytes(n, 1)    // value = {0xBF, 0xF3, 0xC0, 0x83, 0x12, 0x6E, 0x97, 0x8D}
```

? double[] n = {1.23, -7.89}

```
// Convert every single element of the array to byte. For double data, works on 8 bytes sequentially.
value = GetBytes(n)
// value = {0xAE,0x47,0xE1,0x7A,0x14,0xAE,0xF3,0x3F,0x8F,0xC2,0xF5,0x28,0x5C,0x8F,0x1F,0xC0}
value = GetBytes(n, 0)
// value = {0xAE,0x47,0xE1,0x7A,0x14,0xAE,0xF3,0x3F,0x8F,0xC2,0xF5,0x28,0x5C,0x8F,0x1F,0xC0}
value = GetBytes(n, 1)
// value = {0x3F,0xF3,0xAE,0x14,0x7A,0xE1,0x47,0xAE,0xC0,0x1F,0x8F,0x5C,0x28,0xF5,0xC2,0x8F}
```

? bool flag = true

```
value = GetBytes(flag)      //GetBytes converts true to 1, and false to 0.
value = GetBytes(flag, 0)   // value = {1}
                            // value = {1}
                            // Because bool is 1 byte, Endian Parameters are not sufficient.
value = GetBytes(flag, 1)   // value = {1}
```

? bool[] flag = {true, false, true, false, false, true, true}

```
value = GetBytes(flag)      // value = {1, 0, 1, 0, 0, 1, 1}
value = GetBytes(flag, 0)   // value = {1, 0, 1, 0, 0, 1, 1}
value = GetBytes(flag, 1)   // value = {1, 0, 1, 0, 0, 1, 1}
```

? string n = "ABCDEFG" // string to encode in UTF8

```
value = GetBytes(n)     // value = {0x41, 0x42, 0x43, 0x44, 0x45, 0x46, 0x47}
```

```
value = GetBytes(n, 0)      // value = {0x41, 0x42, 0x43, 0x44, 0x45, 0x46, 0x47}
                            // Endian Parameters not valid
value = GetBytes(n, 1)      // value = {0x41, 0x42, 0x43, 0x44, 0x45, 0x46, 0x47}
                            // Endian Parameters not valid
```

```
? string[] n = {"ABC", "DEF", "達明機器人" }
value = GetBytes(n)
// value = {0x41, 0x42, 0x43, 0x44, 0x45, 0x46,
            0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
value = GetBytes(n, 1)
// value = {0x41, 0x42, 0x43, 0x00, 0x00, 0x44, 0x45, 0x46, 0x00, 0x00,
            0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
```

*Conversion of string[] to byte[] can maintain the original contents without separation bytes, but it is unable to turn byte[] back to string[] effectively.

*It is effective to turn byte[] back to string[] by inserting separation bytes (2 consecutive 0x00s) between the elements in the array, but it is possible to find conversion errors if the value of the string come with 0x00 0x00.

Syntax 3

Convert integer (int type) to byte array.

```
byte[] GetBytes(
    int,
    int,
    int
)
```

Parameters

int	The input integer (int type)
int	The input value follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian
int	The input integer value's data type is int32 or int16
0	int32 (Default)
1	int16. If the data does not meets int16 format, int32 will be applied instead.
2	int16. Forced to apply int16 format. For int32 data input, there could be some bytes missing.

Return

byte[]	The byte array formed by input integer. For int32 data, convert with 4 bytes. For int16 data, convert with 2 bytes.

Note

```
value = GetBytes(12345, 0, 0)       // value = {0x39, 0x30, 0x00, 0x00}
value = GetBytes(12345, 0, 1)       // value = {0x39, 0x30}
value = GetBytes(12345, 0, 2)       // value = {0x39, 0x30}
value = GetBytes(0x123456, 0, 0)    // value = {0x56, 0x34, 0x12, 0x00}
value = GetBytes(0x123456, 0, 1)    // value = {0x56, 0x34, 0x12, 0x00}
value = GetBytes(0x123456, 0, 2)    // value = {0x56, 0x34}    // bytes missing
value = GetBytes(0x1234561, 1, 0)   // value = {0x01, 0x23, 0x45, 0x61}
```

```
value = GetBytes(0x1234561, 1, 1) // value = {0x01, 0x23, 0x45, 0x61}
value = GetBytes(0x1234561, 1, 2) // value = {0x45, 0x61}    // bytes missing
```

Syntax 4

Convert the integer array (int[] type) to byte array

```
byte[] GetBytes(
    int[],
    int,
    int
)
```

Parameters

int[]	The input integer array (int[] type)
int	The input integer array follows Little Endian or Big Endian
0	Little Endian (Default)
1	Big Endian
int	The input integer array's data type is int32 or int16
0	int32 (Default)
1	int16. If the data does not meets int16 format, int32 will be applied instead
2	int16. Forced to apply int16 format. For int32 data input, there could be some bytes missing.

Return

byte[]	The byte array formed by input integer array. Every element is converted independently and forms an array. For int32 data, convert with 4 bytes. For int16 data, convert with 2 bytes.

Note

```
i ={10000, 20000, 80000}
value = GetBytes(i, 0, 0)
    // value = {0x10, 0x27, 0x00, 0x00, 0x20, 0x4E, 0x00, 0x00, 0x80, 0x38, 0x01, 0x00}
value = GetBytes(i, 0, 1)   // value = {0x10, 0x27, 0x20, 0x4E, 0x80, 0x38, 0x01, 0x00}
value = GetBytes(i, 0, 2)   // value = {0x10, 0x27, 0x20, 0x4E, 0x80, 0x38}    // bytes missing
value = GetBytes(i, 1, 0)
    // value = {0x00, 0x00, 0x27, 0x10, 0x00, 0x00, 0x4E, 0x20, 0x00, 0x01, 0x38, 0x80}
value = GetBytes(i, 1, 1)   // value = {0x27, 0x10, 0x4E, 0x20, 0x00, 0x01, 0x38, 0x80}
value = GetBytes(i, 1, 2)   // value = {0x27, 0x10, 0x4E, 0x20, 0x38, 0x80}    // bytes missing
```

4.35 GetString()

Convert arbitrary data type to string

Syntax 1

string **GetString**(
    ?,
    int,
    int
)

Parameters

?	The input data. Data type can be int, float, double, bool, string or array.	
int	When the output string's notation is decimal, hexadecimal, or binary, the output string value is in decimal, hexadecimal, or binary.	
	10	decimal, such as 123
	16	hexadecimal, such as 0x7B
	2	binary, such as 0b01111011
	When the input value is a string array, the output string value is in standard string format or not.	
	0 or 10	Automatic detection. If the values in the string come with double quotations or commas, it converse to standard string format.
	1	Mandatory conversion to standard string format
	Other	No conversion
int	The output string format	
	When the output is in decimal	
	0	Never use scientific notation
	1	Use scientific notation when needed.
	When the output is in hexadecimal or binary	
	0	Fill up digits. Add prefix 0x or 0b, e.g. 0x0C or 0b00001100
	1	Fill up digits. No prefix 0x or 0b, e.g. 0C or 00001100
	2	Don't fill up digits. Add prefix 0x or 0b, e.g. 0xC or 0b1100
	3	Don't fill up digits. No prefix 0x or 0b, e.g. C or 1100

Return

string String converted from input data. If the input data cannot be converted, returns empty string.

If the input data is array, every element is converted respectively, and returned in "{ , , }" format

Syntax 2

string **GetString**(
    ?,
    int
)

Note

Similar to Syntax1 with filling up digits and adding prefix 0x or 0b.

GetString(?, 16) => **GetString**(?, 16, 0)

Syntax 3

```
string GetString(
    ?
)
```

Note

Same as syntax 1. The output string's notation defaults to 10 and the output string format defaults to 0.

```
GetString(?)   =>   GetString(?, 10, 0)
GetString(?)   =>   GetString(?, 0, 0)        // supposed ? is a string array
```

```
?    byte n = 123
     value = GetString(n)        // value = "123"
     value = GetString(n, 10)    // value = "123"
     value = GetString(n, 16)    // value = "0x7B"
     value = GetString(n, 2)     // value = "0b01111011"
     value = GetString(n, 16, 3)// value = "7B"
     value = GetString(n, 2, 2)  // value = "0b1111011"

?    byte[] n = {12, 34, 56}
     value = GetString(n)        // value = "{12,34,56}"
     value = GetString(n, 10)    // value = "{12,34,56}"
     value = GetString(n, 16)    // value = "{0x0C,0x22,0x38}"
     value = GetString(n, 2)     // value = "{0b00001100,0b00100010,0b00111000}"
     value = GetString(n, 16, 3)// value = "{C,22,38}"
     value = GetString(n, 2, 2)  // value = "{0b1100,0b100010,0b111000}"

?    int n = 1234
     value = GetString(n)        // value = "1234"
     value = GetString(n, 10)    // value = "1234"
     value = GetString(n, 16)    // value = "0x000004D2"
     value = GetString(n, 2)     // value = "0b00000000000000000000010011010010"
     value = GetString(n, 16, 3)// value = "4D2"
     value = GetString(n, 2, 2)  // value = "0b10011010010"

?    int[] n = {123, 345, -123, -456}
     value = GetString(n)        // value = "{123,345,-123,-456}"
     value = GetString(n, 10)    // value = "{123,345,-123,-456}"
     value = GetString(n, 16)    // value = "{0x0000007B,0x00000159,0xFFFFFF85,0xFFFFFE38}"
     value = GetString(n, 2)     // value = "{0b00000000000000000000001111011,
                                           0b00000000000000000000000101011001,
                                           0b11111111111111111111111110000101,
                                           0b11111111111111111111111000111000}"
     value = GetString(n, 16, 3)// value = "{7B,159,FFFFFF85,FFFFFE38}"
     value = GetString(n, 2, 2)  // value = "{0b1111011,
                                           0b101011001,
                                           0b11111111111111111111111110000101,
                                           0b11111111111111111111111000111000}"

?    float n = 12.34
```

```
value = GetString(n)        // value = "12.34"
value = GetString(n, 10)    // value = "12.34"
value = GetString(n, 16)    // value = "0x414570A4"
value = GetString(n, 2)     // value = "0b01000001010001010111000010100100"
value = GetString(n, 16, 3)// value = "414570A4"
value = GetString(n, 2, 2)  // value = "0b10000010100010101111000010100100"

?   float[] n = {123.4, 345.6, -123.4, -456.7}
value = GetString(n)        // value = "{123.4,345.6,-123.4,-456.7}"
value = GetString(n, 10)    // value = "{123.4,345.6,-123.4,-456.7}"
value = GetString(n, 16)    // value = "{0x42F6CCCD,0x43ACCCCD,0xC2F6CCCD,0xC3E4599A}"
value = GetString(n, 16, 3)// value = "{42F6CCCD,43ACCCCD,C2F6CCCD,C3E4599A}"

?   double n = 12.34
value = GetString(n)        // value = "12.34"
value = GetString(n, 10)    // value = "12.34"
value = GetString(n, 16)    // value = "0x4028AE147AE147AE"
value = GetString(n, 16, 3)// value = "4028AE147AE147AE"

?   double[] n = {123.45, 345.67, -123.48, -456.79}
value = GetString(n)        // value = "{123.45,345.67,-123.48,-456.79}"
value = GetString(n, 10)    // value = "{123.45,345.67,-123.48,-456.79}"
value = GetString(n, 16)    // value = "{0x405EDCCCCCCCCCCD,0x40759AB851EB851F,
                                0xC05EDEB851EB851F,0xC07C8CA3D70A3D71}"
value = GetString(n, 16, 3)     // value = "{405EDCCCCCCCCCCD,40759AB851EB851F,
                                C05EDEB851EB851F,C07C8CA3D70A3D71}"

?   bool n = true
value = GetString(n)        // value = "true"
value = GetString(n, 16)    // value = "true"
value = GetString(n, 2)     // value = "true"
value = GetString(n, 16, 3)// value = "true"

?   bool[] n = {true, false, true, false, false, true}
value = GetString(n)        // value = "{true,false,true,false,false,true}"
value = GetString(n, 16)    // value = "{true,false,true,false,false,true}"
value = GetString(n, 2)     // value = "{true,false,true,false,false,true}"
value = GetString(n, 16, 3)// value = "{true,false,true,false,false,true}"

?   string n = "1234567890"
value = GetString(n)        // value = "1234567890"
value = GetString(n, 16)    // value = "1234567890"
value = GetString(n, 2)     // value = "1234567890"
value = GetString(n, 16, 3)// value = "1234567890"

?   string[] n = {"123.45", "345.67", "-12""3.48", "-45A6.79"}
value = GetString(n)        // value = "{123.45,345.67,-12""3.48,-45A6.79}"
value = GetString(n, 1)     // value = "{"123.45","345.67","-12""3.48","-45A6.79"}"
```

```
value = GetString(n, 2)      // value = "{123.45,345.67,-12"3.48,-45A6.79}"
                             // -12""3.48 displayed as -12"3.48
value = GetString(n, 16, 3)  // value = "{123.45,345.67,-12""3.48,-45A6.79}"
value = GetString(n, 10, 3)  // value = "{123.45,345.67,"-12""3.48",-45A6.79}"
                             //use automatic detection as the default
```

Syntax 4

```
string GetString(
    ?,
    string,
    int,
    int
)
```

Parameters

?	The input data. Data type can be int, float, double, bool, string or array.
string	Separator for output string (Only effective to array input)
int	When the output string's notation is decimal, hexadecimal, or binary, the output string value is in decimal, hexadecimal, or binary.
10	decimal, such as 123
16	hexadecimal, such as 0x7B
2	binary, such as 0b01111011
	When the input value is a string array, the output string value is in standard string format or not.
0 or 10	Automatic detection. If the values in the string come with double quotations or separation symbols, it converse to standard string format.
1	Mandatory conversion to standard string format
Other	No conversion
int	The output string format
	When the output is in decimal
0	Never use scientific notation
1	Use scientific notation when needed.
	When the output is in hexadecimal or binary
0	Fill up digits. Add prefix 0x or 0b, e.g. 0x0C or 0b00001100
1	Fill up digits. No prefix 0x or 0b, e.g. 0C or 00001100
2	Don't fill up digits. Add prefix 0x or 0b, e.g. 0xC or 0b1100
3	Don't fill up digits. No prefix 0x or 0b, e.g. C or 1100

Return

string	String converted from input data. If the input data cannot be converted, returns empty string.
	If the input data is array, every element is converted respectively, and returned as a string with the assigned separator

Syntax 5

```
string GetString(
    ?,
    string,
    int
)
```

Note

Same as Syntax 4 with filling up digits and adding prefix 0x or 0b

GetString(?, str, 16) => **GetString**(?, str, 16, 0)

Syntax 6

```
string GetString(
    ?,
    string
)
```

Note

Same as Syntax 4. The output string's notation defaults to 10 and the output string format defaults to 0.

GetString(?) => **GetString**(?, 10, 0)

GetString(?) => **GetString**(?, 0, 0) // supposed ? is a string array

```
?   byte n = 123
    value = GetString(n)            // value = "123"
    value = GetString(n, ";", 10)   // value = "123"
    value = GetString(n, "-", 16)   // value = "0x7B"
    value = GetString(n, "#", 2)    // value = "0b01111011"
    value = GetString(n, ",", 16, 3) // value = "7B"
    value = GetString(n, ",", 2, 2)  // value = "0b1111011"
    * Separator is effective to array input only.

?   byte[] n = {12, 34, 56}
    value = GetString(n, "-")           // value = "12-34-56"
    value = GetString(n, Ctrl("\r\n"), 10)// value = "12\u0D0A34\u0D0A56"
    value = GetString(n, newline, 16)   // value = "0x0C\u0D0A0x22\u0D0A0x38"
    value = GetString(n, NewLine, 2)    // value =
                                        "0b00001100\u0D0A0b00100010\u0D0A0b00111000"
    value = GetString(n, "-", 16, 3)    // value = "C-22-38"
    value = GetString(n, "-", 2, 2)     // value = "0b1100-0b100010-0b111000"
    * \u0D0A is Newline control character, not string value.

?   string[] n = {"123.45", "345.67", "-12""3.48", "-45A6.79"}
    value = GetString(n, "-")       // value = "123.45-345.67-"-12""3.48"-"-45A6.79""
    value = GetString(n, "-", 1)    // value = ""123.45"-"345.67"-"-12""3.48"-"-45A6.79""
    value = GetString(n, "-", 2)    // value = "123.45-345.67--12"3.48--45A6.79"
                                    // Troubled for identifying the separation symbols and the negative signs.
```

Syntax 7

```
string GetString(
    ?,
    string,
    string,
    int,
    int
)
```

Parameters

? The input data. Data type can be int, float, double, bool, string or array.

string The index of the output string for array input. (Only effective to ? as array type data)
* Support numeric format strings

string Separator for output string (Only effective to array input)

int The output string's notation is decimal, hexadecimal or binary (Can be only applied to hexadecimal or binary number)
10 decimal, such as 123
16 hexadecimal, such as 0x7B
2 binary, such as 0b01111011
String's notation
123 decimal
0x7F hexadecimal
0b101 binary
When the input value is a string array, the output string value is in standard string format or not.
0 or 10 Automatic detection. If the values in the string come with double quotations or separation symbols, it converse to standard string format.
1 Mandatory conversion to standard string format
Other No conversion

int The output string format
When the output is in decimal
0 Never use scientific notation
1 Use scientific notation when needed.
When the output is in hexadecimal or binary
0 Fill up digits. Add prefix 0x or 0b, e.g. 0x0C or 0b00001100
1 Fill up digits. No prefix 0x or 0b, e.g. 0C or 00001100
2 Don't fill up digits. Add prefix 0x or 0b, e.g. 0xC or 0b1100
3 Don't fill up digits. No prefix 0x or 0b, e.g. C or 1100

Return

string Converse the value to the string to return. If unable to converse, it returns an empty string.
If the type is array, elements in the array will be conversed to strings with prefixes of the element index value format string separated by separation symbols to return.
There will be no braces.

Syntax 8

string **GetString**(
?,
string,
string,
int
)

Note

Similar to Syntax7 with filling up digits and adding prefix.
GetString(?, str, str, 16) => **GetString**(?, str, str, 16, 0)

Syntax 9

```
string GetString(
    ?,
    string,
    string
)
```

Note

Similar to Syntax7 with decimal output, with filling up digits and adding prefix.

GetString(?, str, str) => **GetString**(?, str, str, 10, 0)

```
?   byte n = 123
    value = GetString(n)                    // value = "123"
    value = GetString(n, "[0]=", ";", 10)   // value = "123"
    value = GetString(n, "[0]=", "-", 16)   // value = "0x7B"
    value = GetString(n, "[0]=", "#", 2)    // value = "0b01111011"
```

* Index and sepapator are only effective to array input.

```
?   byte[] n = {12, 34, 56}
    value = GetString(n, "[0]=", "-")               // value = "[0]=12-[1]=34-[2]=56"
    value = GetString(n, "[0]=", Ctrl("\r\n"), 10)  // value = "[0]=12\u0D0A[1]=34\u0D0A[2]=56"
    value = GetString(n, "[0]=", newline, 16)       // value = "[0]=0x0C\u0D0A[1]=0x22\u0D0A[2]=0x38"
    value = GetString(n, "[0]=", "-", 16, 3)        // value = "[0]=C-[1]=22-[2]=38"
    value = GetString(n, "[0]=", "-", 2, 2)         // value = "[0]=0b1100-[1]=0b100010-[2]=0b111000"
```

* "[0]=" Support numeric format strings
* \u0D0A is Newline control character, not string value.

4.36 GetToken()

Retrieve a substring from input string, or the sub-array from the input byte[] array

Syntax 1

string **GetToken**(
string,
string,
string,
int,
int
)

Parameters

string	Input string	
string	Prefix. The leading element of the substring	
string	Suffix. The trailing element of the substring	
int	The number of the matched substtring to retrieve	
	>=1	Retrieve the nth matched substring
	-1	Retrieve the last matched substring
int	Remove options	
	0 (default)	The 1st matched not in the start of the input string, and not remove the prefix and the suffix.
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string String formed by part of the input string
If the prefix and suffix are empty strings, returns the input string
If the number of the matched substrings <=0 or larger than the number of the total matched substrings, returns empty string
If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 2

string **GetToken**(
string,
string,
string,
int
)

Note

Similar to Syntax1 with reserving prefix and suffix.
GetToken(str,str,str,1) => **GetToken**(str,str,str,1,0)

Syntax 3

string **GetToken**(
string,
string,

```
        string
)
```

Note

Similar to Syntax1 with returning the first occurrence, and reserving prefix and suffix.

GetToken(str,str,str) => **GetToken**(str,str,str,1,0)

```
string n = "$abcd$1234$ABCD$"
value = GetToken(n, "", "", 0)          // value = "$abcd$1234$ABCD$"
value = GetToken(n, "$", "$")           // value = "$abcd$"
value = GetToken(n, "$", "$", 0)        // value = ""
value = GetToken(n, "$", "$", 1)        // value = "$abcd$"
value = GetToken(n, "$", "$", 2)        // value = "$ABCD$"
value = GetToken(n, "$", "$", 3)        // value = ""
value = GetToken(n, "$", "$", -1, 1)    // value = "ABCD"
value = GetToken(n, "$", "$", 1, 1)     // value = "abcd"
value = GetToken(n, "$", "$", 2, 1)     // value = "ABCD"
value = GetToken(n, "$", "", 1)         // value = "$abcd"
value = GetToken(n, "$", "", 2)         // value = "$1234"
value = GetToken(n, "$", "", 3)         // value = "$ABCD"
value = GetToken(n, "$", "", 4)         // value = "$"
value = GetToken(n, "", "$", 1)         // value = "$"
value = GetToken(n, "", "$", 2)         // value = "abcd$"
value = GetToken(n, "", "$", 3)         // value = "1234$"
value = GetToken(n, "", "$", 4)         // value = "ABCD$"
string n = "$abcd$1234$ABCD$" + Ctrl("\r\n") + "56\r\n78$"
value = GetToken(n, "$", Ctrl("\r\n"), 1)  // value = "$abcd$1234$ABCD$\u0D0A"
value = GetToken(n, "$", newline, 2)            // value = ""
value = GetToken(n, "$", NewLine, 1, 1)// value = "abcd$1234$ABCD$"
                                        // Remove prefix and suffix
value = GetToken(n, Ctrl("\r\n"), "$", 1)  // value = "\u0D0A56\r\n78$"
value = GetToken(n, newline, "$", 2)       // value = ""
value = GetToken(n, NewLine, "$", 1, 1)// value = "56\r\n78"
```

* \u0D0A is Newline control character, not string value.

```
string n = "#abcd$1234#ABCD$5678#"
value = GetToken(n, "", "", 0)          // value = "#abcd$1234#ABCD$5678#"
value = GetToken(n, "$", "$")           // value = "$1234#ABCD$"
value = GetToken(n, "$", "$", 0)        // value = ""
value = GetToken(n, "$", "$", 1)        // value = "$1234#ABCD$"
value = GetToken(n, "$", "$", 2)        // value = ""
value = GetToken(n, "$", "$", 3)        // value = ""
value = GetToken(n, "$", "$", -1, 0)    // value = "$1234#ABCD$"
value = GetToken(n, "$", "$", -1, 1)    // value = "1234#ABCD"
value = GetToken(n, "$", "$", 1, 1)     // value = "1234#ABCD"
value = GetToken(n, "$", "$", 2, 1)     // value = ""
value = GetToken(n, "$", "", 1)         // value = "$1234#ABCD"
value = GetToken(n, "$", "", 2)         // value = "$5678#"
value = GetToken(n, "$", "", 3)         // value = ""
value = GetToken(n, "$", "", 4)         // value = ""
```

```
value = GetToken(n, "", "$", 1)        // value = "#abcd$"
value = GetToken(n, "", "$", 2)        // value = "1234#ABCD$"
value = GetToken(n, "", "$", 3)        // value = ""
value = GetToken(n, "", "$", 4)        // value = ""
value = GetToken(n, "$", "$", 1, 2)    // value = ""
                                       // The string matched $ not in the start of the input string.
value = GetToken(n, "$", "$", -1, 2)   // value = ""
                                       // The string matched $ not in the start of the input string.
value = GetToken(n, "#", "", 1, 3)     // value = "abcd$1234"
value = GetToken(n, "#", "", 1, 2)     // value = "#abcd$1234"
value = GetToken(n, "#", "", 2, 2)     // value = "#ABCD$5678"
value = GetToken(n, "#", "", 3, 2)     // value = "#"
value = GetToken(n, "#", "", 4, 2)     // value = ""
value = GetToken(n, "#", "", -1, 2)    // value = "#"
value = GetToken(n, "#", "", -1, 3)    // value = ""
value = GetToken(n, "#", "$", 1, 2)    // value = "#abcd$"
value = GetToken(n, "#", "$", 1, 3)    // value = "abcd"
```

Syntax 4

```
string GetToken(
    string,
    byte[],
    byte[],
    int,
    int
)
```

Parameters

string	Input string	
byte[]	Prefix. The leading element of the substring, byte[] type	
byte[]	Suffix. The trailing element of the substring, byte[] type	
int	The number of the matched substtring to retrieve	
	>=1	Retrieve the nth matched substring
	-1	Retrieve the last matched substring
int	Remove options	
	0 (default)	The 1st matched not in the start of the input string, and not remove the prefix and the suffix.
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string	String formed by part of the input string If the prefix and suffix are empty strings, returns the input string If the number of the matched substrings <=0 or larger than the number of the totol matached substrings, returns empty string If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 5

```
string GetToken(
    string,
    byte[],
    byte[],
    int
)
```

Note

Similar to Syntax4 with reserving prefix and suffix

GetToken(str,byte[],byte[],1) => **GetToken**(str,byte[],byte[],1,0)

Syntax 6

```
string GetToken(
    string,
    byte[],
    byte[]
)
```

Note

Similar to Syntax 4 with the first occurrence and reserving prefix and suffix

GetToken(str,byte[],byte[]) => **GetToken**(str,byte[],byte[],1,0)

```
string n = "$abcd$1234$ABCD$"
byte[] bb0 = {}, bb1 = {0x24}      // 0x24 is $
value = GetToken(n, bb0, bb0, 0)    // value = "$abcd$1234$ABCD$"
value = GetToken(n, bb1, bb1)       // value = "$abcd$"
value = GetToken(n, bb1, bb1, 0)    // value = ""
value = GetToken(n, bb1, bb1, 1)    // value = "$abcd$"
value = GetToken(n, bb1, bb1, 2)    // value = "$ABCD$"
value = GetToken(n, bb1, bb1, 3)    // value = ""
value = GetToken(n, bb1, bb1, 1, 1) // value = "abcd"
value = GetToken(n, bb1, bb1, 2, 1) // value = "ABCD"
value = GetToken(n, bb1, bb0, 1)    // value = "$abcd"
value = GetToken(n, bb1, bb0, 2)    // value = "$1234"
value = GetToken(n, bb1, bb0, 3)    // value = "$ABCD"
value = GetToken(n, bb1, bb0, 4)    // value = "$"
value = GetToken(n, bb0, bb1, 1)    // value = "$"
value = GetToken(n, bb0, bb1, 2)    // value = "abcd$"
value = GetToken(n, bb0, bb1, 3)    // value = "1234$"
value = GetToken(n, bb0, bb1, 4)    // value = "ABCD$"

string n = "$abcd$1234$ABCD$" + Ctrl("\r\n") + "56\r\n78$"
byte[] bb0 = {0x0D,0x0A}, bb1 = {0x24}  // 0x24 is $       // 0x0D,0x0A is \u0D0A
value = GetToken(n, bb1, bb0, 1)    // value = "$abcd$1234$ABCD$\u0D0A"
value = GetToken(n, bb1, bb0, 2)    // value = ""
value = GetToken(n, bb1, bb0, 1, 1)       // value = "abcd$1234$ABCD$"
                                          // Removing the prefix and the suffix
value = GetToken(n, bb0, bb1, 1)    // value = "\u0D0A56\r\n78$"
value = GetToken(n, bb0, bb1, 2)    // value = ""
value = GetToken(n, bb0, bb1, 1, 1)       // value = "56\r\n78"
```

* \u0D0A is the Newline control character, not the string content.

Syntax 7

byte[] **GetToken**(
byte[],
string,
string,
int,
int
)

Parameters

byte[] The input byte[]

string Prefix. The leading element of the output byte[], byte[] type

string Suffix. The trailing element of the output byte[], byte[] type

int The number of the matched substring to retrieve

>=1 Retrieve the nth matched substring

-1 Retrieve the last matched substring

int Remove options

0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix.
(default)

1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.

2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.

3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

byte[] The byte[] formed from part of the input byte[]
If the prefix and suffix are empty, returns the input array
If the number of the matched substrings <=0 or larger than the number of the total matched substrings, returns empty array
If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 8

byte[] **GetToken**(
byte[],
string,
string,
int
)

Note

Similar to Syntax7 with reserving prefix and suffix
GetToken(byte[],str,str,1) => **GetToken**(byte[],str,str,1,0)

Syntax 9

byte[] **GetToken**(
byte[],
string,
string
)

Note

Similar to Syntax7 with returning the first occurrence, and reserving prefix and suffix.

GetToken(byte[],str,str) => **GetToken**(byte[],str,str,1,0)

```
string s ="$abcd$1234$ABCD$"
byte[] n = GetBytes(s)
value = GetToken(n, "", "", 0)
        // value =
        {0x24,0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24}
value = GetToken(n, "$", "$")       // value = {0x24,0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, "$", "$", 0)    // value = {}
value = GetToken(n, "$", "$", 1)    // value = {0x24,0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, "$", "$", 2)    // value = {0x24,0x41,0x42,0x43,0x44,0x24}
value = GetToken(n, "$", "$", 1, 1) // value = {0x61,0x62,0x63,0x64}
value = GetToken(n, "$", "$", 2, 1) // value = {0x41,0x42,0x43,0x44}
value = GetToken(n, "$", "", 1)     // value = {0x24,0x61,0x62,0x63,0x64}
value = GetToken(n, "$", "", 2)     // value = {0x24,0x31,0x32,0x33,0x34}
value = GetToken(n, "$", "", 3)     // value = {0x24,0x41,0x42,0x43,0x44}
value = GetToken(n, "$", "", 4)     // value = {0x24}
value = GetToken(n, "", "$", 1)     // value = {0x24}
value = GetToken(n, "", "$", 2)     // value = {0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, "", "$", 3)     // value = {0x31,0x32,0x33,0x34,0x24}
value = GetToken(n, "", "$", 4)     // value = {0x41,0x42,0x43,0x44,0x24}
string s ="$abcd$1234$ABCD$" + Ctrl("\r\n") + "56\r\n78$"
byte[] n = GetBytes(s)
value = GetToken(n, "$", Ctrl("\r\n"), 1)
    // value =
    {0x24,0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24,0x0D,0x0A}
value = GetToken(n, "$", Ctrl("\r\n"), 1, 1)
    // value = {0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24}
    // Removing prefix and suffix
value = GetToken(n, Ctrl("\r\n"), "$", 1)
    // value = {0x0D,0x0A,0x35,0x36,0x5C,0x72,0x5C,0x6E,0x37,0x38,0x24}
value = GetToken(n, Ctrl("\r\n"), "$", 1, 1)
    // value = {0x35,0x36,0x5C,0x72,0x5C,0x6E,0x37,0x38}
```

Syntax 10

```
byte[] GetToken(
    byte[],
    byte[],
    byte[],
    int,
    int
)
```

Parameters

byte[]	The input byte[] array
byte[]	Prefix. The leading element of the output byte[]
byte[]	Suffix. The trailing element of the output byte[]
int	The number of the matched substring to retrieve
>=1	Retrieve the nth matched substring

-1 Retrieve the last matched substring

int Remove options

0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)

1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.

2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.

3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

byte[] The byte[] formed from part of the input byte[]
If the prefix and suffix are empty, returns the input array
If the number of the matched substrings <=0 or larger than the number of total matched substrings, returns empty array
If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 11

```
byte[] GetToken(
    byte[],
    byte[],
    byte[],
    int
)
```

Note

Similar to Syntax10 with reserving the prefix and suffix
GetToken(byte[],byte[],byte[],1) => **GetToken**(byte[],byte[],byte[],1,0)

Syntax 12

```
byte[] GetToken(
    byte[],
    byte[],
    byte[]
)
```

Note

Similar to Syntax10 with returning the first occurrence, and reserving prefix and suffix.
GetToken(byte[],byte[],byte[]) => **GetToken**(byte[],byte[],byte[],1,0)

```
string s ="$abcd$1234$ABCD$"
byte[] n = GetBytes(s)
byte[] bb0 = {}, bb1 = {0x24}      // 0x24 is $
value = GetToken(n, bb0, bb0, 0)
        // value =
        {0x24,0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24}
value = GetToken(n, bb1, bb1) // value = {0x24,0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, bb1, bb1, 0)    // value = {}
value = GetToken(n, bb1, bb1, 1)    // value = {0x24,0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, bb1, bb1, 2)    // value = {0x24,0x41,0x42,0x43,0x44,0x24}
value = GetToken(n, bb1, bb1, 1, 1)// value = {0x61,0x62,0x63,0x64}
value = GetToken(n, bb1, bb1, 2, 1)// value = {0x41,0x42,0x43,0x44}
value = GetToken(n, bb1, bb0, 1)    // value = {0x24,0x61,0x62,0x63,0x64}
```

```
value = GetToken(n, bb1, bb0, 2)    // value = {0x24,0x31,0x32,0x33,0x34}
value = GetToken(n, bb1, bb0, 3)    // value = {0x24,0x41,0x42,0x43,0x44}
value = GetToken(n, bb0, bb1, 1)    // value = {0x24}
value = GetToken(n, bb0, bb1, 2)    // value = {0x61,0x62,0x63,0x64,0x24}
value = GetToken(n, bb0, bb1, 3)    // value = {0x31,0x32,0x33,0x34,0x24}
string s ="$abcd$1234$ABCD$" + Ctrl("\r\n") + "56\r\n78$"
byte[] n = GetBytes(s)
byte[] bb0 = {0x0D,0x0A}, bb1 = {0x24}
value = GetToken(n, bb1, bb0, 1)
    // value =
    {0x24,0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24,0x0D,0x0A}
value = GetToken(n, bb1, bb0, 1, 1)
    // value = {0x61,0x62,0x63,0x64,0x24,0x31,0x32,0x33,0x34,0x24,0x41,0x42,0x43,0x44,0x24}
    // Remove prefix and suffix
value = GetToken(n, bb0, bb1, 1)
    // value = {0x0D,0x0A,0x35,0x36,0x5C,0x72,0x5C,0x6E,0x37,0x38,0x24}
value = GetToken(n, bb0, bb1, 1, 1)
    // value = {0x35,0x36,0x5C,0x72,0x5C,0x6E,0x37,0x38}
```

4.37 GetAllTokens()

Retrieve all the substrings from input string, which meets the given condition

Syntax 1

```
string[] GetAllTokens(
    string,
    string,
    string,
    int
)
```

Parameters

string	Input string	
string	Prefix. The leading element of the substring	
string	Suffix. The trailing element of the substring	
int	Remove options	
	0 (default)	The 1st matched not in the start of the input string, and not remove the prefix and the suffix.
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string[]	String array formed from retrieving all the substrings from input string If the prefix and suffix are empty, returns the input array If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 2

```
string[] GetAllTokens(
    string,
    string,
    string
)
```

Note

Similar to Syntax1 with reserving prefix and suffix

GetAllTokens(str,str,str) => **GetAllTokens**(str,str,str,0)

```
string n = "$abcd$1234$ABCD$"
value = GetAllTokens(n, "", "")          // value = {"$abcd$1234$ABCD$"}
value = GetAllTokens(n, "$", "$")        // value = {"$abcd$", "$ABCD$"}
value = GetAllTokens(n, "$", "$", 1)     // value = {"abcd", "ABCD"}
value = GetAllTokens(n, "$", "")         // value = {"$abcd", "$1234", "$ABCD", "$"}
value = GetAllTokens(n, "", "$", 1)      // value = {"", "abcd", "1234", "ABCD"}

string n = "#abcd$1234#ABCD$5678#"
value = GetAllTokens(n, "", "", 0)   // value = {"#abcd$1234#ABCD$5678#"}
value = GetAllTokens(n, "$", "", 0)  // value = {"$1234#ABCD","$5678#"}
value = GetAllTokens(n, "$", "", 1)  // value = {"1234#ABCD","5678#"}
value = GetAllTokens(n, "$", "", 2)  // value = {}
```

```
                                        // $ is not in the start of the input string. Returns an empty array.
value = GetAllTokens(n, "$", "", 3)  // value = {}
                                        // $ is not in the start of the input string. Returns an empty array.
value = GetAllTokens(n, "$", "$", 0)// value = {"$1234#ABCD$"}
value = GetAllTokens(n, "$", "$", 1)// value = {"1234#ABCD"}
value = GetAllTokens(n, "$", "$", 2)// value = {}
                                        // $ is not in the start of the input string. Returns an empty array.
value = GetAllTokens(n, "$", "$", 3)// value = {}
                                        // $ is not in the start of the input string. Returns an empty array.
value = GetAllTokens(n, "#", "", 0)  // value = {"#abcd$1234", "#ABCD$5678", "#"}
value = GetAllTokens(n, "#", "", 1)  // value = {"abcd$1234", "ABCD$5678", ""}
value = GetAllTokens(n, "#", "", 2)  // value = {"#abcd$1234", "#ABCD$5678", "#"}
value = GetAllTokens(n, "#", "", 3)  // value = {"abcd$1234", "ABCD$5678", ""}
value = GetAllTokens(n, "#", "$", 0)// value = {"#abcd$", "#ABCD$"}
value = GetAllTokens(n, "#", "$", 1)// value = {"abcd", "ABCD"}
value = GetAllTokens(n, "#", "$", 2)// value = {"#abcd$", "#ABCD$"}
value = GetAllTokens(n, "#", "$", 3)// value = {"abcd", "ABCD"}
value = GetAllTokens(n, "", "$", 0)  // value = {"#abcd$", "1234#ABCD$"}
value = GetAllTokens(n, "", "$", 1)  // value = {"#abcd", "1234#ABCD"}
value = GetAllTokens(n, "", "$", 2)  // value = {"#abcd$", "1234#ABCD$"}
value = GetAllTokens(n, "", "$", 3)  // value = {"#abcd", "1234#ABCD"}
value = GetAllTokens(n, "", "#", 0)  // value = {"#", "abcd$1234#", "ABCD$5678#"}
value = GetAllTokens(n, "", "#", 1)  // value = {"", "abcd$1234", "ABCD$5678"}
value = GetAllTokens(n, "", "#", 2)  // value = {"#", "abcd$1234#", "ABCD$5678#"}
value = GetAllTokens(n, "", "#", 3)  // value = {"", "abcd$1234", "ABCD$5678"}
```


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4.38 GetNow()

Get the current system time

Syntax 1

string **GetNow**(
    string
)

Parameters

string The date and time format strings defining the text representation of a date and time value. The definition of each specifier is listed below. The strings not included will remains the same.

d	The day of the month, from 1 through 31.
dd	The day of the month, from 01 through 31.
ddd	The abbreviated name of the day of the week.
dddd	The full name of the day of the week.
f	The tenths of a second in a date and time value.
ff	The hundredths of a second in a date and time value.
fff	The milliseconds in a date and time value.
ffff	The ten thousandths of a second in a date and time value.
h	The hour, using a 12-hour clock from 1 to 12.
hh	The hour, using a 12-hour clock from 01 to 12.
H	The hour, using a 24-hour clock from 0 to 23.
HH	The hour, using a 24-hour clock from 00 to 23.
m	The minute, from 0 through 59.
mm	The minute, from 00 through 59.
M	The month, from 1 through 12.
MM	The month, from 01 through 12.
MMM	The abbreviated name of the month.
MMMM	The full name of the month.
s	The second, from 0 through 59.
ss	The second, from 00 through 59.
t	The first character of the AM/PM designator.
tt	The AM/PM designator.
y	The year, from 0 to 99.
yy	The year, from 00 to 99.
yyyy	The year as a four-digit number.
/	The date separator.

Return

string Current date and time. If there is errors in format setting, the default format will be applied as MM/dd/yyyy HH:mm:ss.

Note

```
value = GetNow("MM/dd/yyyy HH:mm:ss")          // value = 08/15/2017 13:40:30
value = GetNow("yyyy/MM/dd HH:mm:ss.ffff")     // value = 2017/08/15 13:40:30.1337
value = GetNow("yyyy-MM-dd hh:mm:ss tt")       // value = 2017-08-15 01:40:30 PM
```

Syntax 2

string **GetNow**(

)

Parameters

void No format defined. Default format "MM/dd/yyyy HH:mm:ss" will be applied

Return

string Current date and time.

Note

```
value = GetNow()        // value = 08/15/2017 13:40:30
```

4.39 GetNowStamp()

Get the total run time or difference in total run time

Syntax 1

int **GetNowStamp**(
)

Parameters

void No parameter

Return

int The total run time of the current project in ms. The upper limit is 2147483647 ms

< 0 Over flow, invalid total run time

Note

```
value = GetNowStamp()        // value = 2147483647
… others …
value = GetNowStamp()        // value = -1      // Over flow
```

Syntax 2

double **GetNowStamp**(
bool
)

Parameters

bool Use double format to record project's total run time or not?

true Use double type, the upper limit is 9223372036854775807 ms

false Use int32 type, the upper limit is 2147483647 ms

Return

double The total run time of the current project

< 0 Over flow. Invalid total run time.

Note

```
value = GetNowStamp(false)        // value = 2147483647
… others …
value = GetNowStamp(false)        // value = -1      // Over flow
value = GetNowStamp(true)         // value = 3147483647
```

Syntax 3

int **GetNowStamp**(
int
)

Parameters

int Previous recorded run time in ms

Return

int The difference between the current run time and the input run time in ms.
Run time difference = current run time – input run time

< 0 Invalid run time difference, caused by input run time larger than current run time, or over flow.

Note

```
value = GetNowStamp()        // value = 2147483546
```

```
… others … (After 100ms)
diff = GetNowStamp(value)      // diff = 100
… others … (After 200ms)
diff = GetNowStamp(value)      // diff = -1        // Value is over 2147483647
```

Syntax 4

```
double GetNowStamp(
    double
)
```

Parameters

double	Previous recorded run time in ms

Return

double	The difference between the current run time and the input run time in ms. Run time difference = current run time – input run time
< 0	Invalid run time difference, caused by input run time larger than current run time, or over flow.

Note

```
value = GetNowStamp()          // value = 2147483546
… others … (After 100ms)
diff = GetNowStamp(value)      // diff = 100
… others … (After 200ms)
diff = GetNowStamp(value)      // diff = 200
```

Syntax 5

```
bool GetNowStamp(
    int,
    int
)
```

Parameters

int	Previous recorded run time in ms
int	The expected run time difference

Return

bool	The time difference between current run time and input run time is larger than the expected run time difference or not.
true	(Current run time – input run time) >= expected run time Or Time difference smaller than zero or over flow
false	(Current run time – input run time) < expected run time

Note

```
value = GetNowStamp()          // value = 41730494
… others … (After 60ms)
flag = GetNowStamp(value, 100) // diff = 60      // flag = false
… others … (After 60ms)
flag = GetNowStamp(value, 100) // diff = 120     // flag = true
```

Syntax 6

```
bool GetNowStamp(
    double,
    double
```

)

Parameters

double	Previous recorded run time in ms
double	The expected run time difference

Return

bool	The time difference between current run time and input run time is larger than the expected run time difference or not.
	true (Current run time – input run time) >= expected run time
	Or Time difference smaller than zero or over flow
	false (Current run time – input run time) < expected run time

Note

```
value = GetNowStamp()          // value = 41730494
… others … (After 60ms)
flag = GetNowStamp(value, 100)   // diff = 60      // flag = false
… others … (After 60ms)
flag = GetNowStamp(value, 100)   // diff = 120     // flag = true
```

4.40 GetVarValue()

Retrieve the value of the variable value. Users can use the string to combine the variable names, and then retrieve the combined value of the variables.

Syntax 1

? **GetVarValue**(
    string
)

Parameters

string The name of the variable

Return

? Return the value of the variable. The return type goes by the definition of the variable.

Return an error if the variable is not existed.

Note

```
string var_s1 = "Hello World"
string var_h = " var_s1"
string var_t = " var_s"

string var_re = var_t                  // var_re = " var_s"
var_re = var_t + "1"                   // var_re = " var_s" + "1" = " var_s1"
var_re = GetVarValue("var_h")          // var_re = " var_s1"
var_re = GetVarValue(var_h)            // var_re = "Hello World"    // var_h = " var_s1"
                                       // Retrieve the value of var_s1
var_re = GetVarValue(var_t + "1")      // var_re = "Hello World"    // var_b + "1" = " var_s1"
                                       // Retrieve the value of var_s1
var_re = GetVarValue(var_t)            // Error     // var_t = " var_s"
                                       //Retrieve the value of var_s, but the variable is not existed.

string s
int[] var_array0 = {10, 11, 12, 13, 14}
int[] var_array1 = {20, 21, 22, 23, 24}
for (int i = 0; i < 2; i++)
{
int[] v = GetVarValue("var_array" + i)
for (int j = 0; j < Length(v) ; j++) s += v[j] + ", "
s += newline
}
Display(s)          // 10, 11, 12, 13, 14, \u0D0A20, 21, 22, 23, 24, \u0D0A
```

* \u0D0A is a written line break, not a string value.

4.41 SetVarValue()

For variable value settings, users can use a string to combine the variable names to set the variable value of the combined variable names.

Syntax 1

```
bool SetVarValue(
    string,
    ?
)
```

Parameters

string	The name of the variable
?	The variable value

Return

bool	The variable setting value. Return True if successful; False if unsuccessful. Returns an error if the variable does not exist or cannot convert legitimately.

Note

```
string var_s1 = "Hello World"
SetVarValue("var_s1", "Hi World")    // var_s1 = "Hi World"
int var_k = 100
SetVarValue("var_k", 200)        // var_k = 200
SetVarValue("var_k", 2.3)        // var_k = 2       // Since 2.3 converting to the int type
SetVarValue("var_k", "2.3")      // var_k = 2       // Since "2.3" converting to the int type

SetVarValue("var_k", true)       // Error
SetVarValue("var_k", "XYZ")      // Error

int[] var_array0 = {10, 11, 12, 13, 14}
int[] var_array1 = {20, 21, 22, 23, 24}
for (int i = 0; i < 2; i++)
{
    int[] v = GetVarValue("var_array" + i)      // Retrieve var_array0 or var_array1
    for (int j = 0; j < Length(v) ; j++)
        v[j] += 100                             // +100 for each element in int[] v
    SetVarValue("var_array" + i, v)             // Set the value of int[] v to var_array0 or var_array1.
}
Display(var_array0)          // {110,111,112,113,114}
Display(var_array1)          // {120,121,122,123,124}
```

4.42 Length()

Acquire the number of byte of input data, length of string or length of array (number of elements in array)

Syntax 1

int **Length**(
    ?
)

Parameters

? The input data. The available data types are integer, floating-point, boolean, string, or array.

Return

int Length of data
For input as integer, floating-point number, and boolean, returns the number of byte.
For input as string, returns the length of string.
For input as array, returns the number of element in array

Note

```
? byte n = 100
    value = Length(n)      // value = 1
    value = Length(100)    // value = 1
? int n = 400
    value = Length(n)      // value = 4
    value = Length(400)    // value = 4
? float n = 1.234
    value = Length(n)          // value = 4
    value = Length(1.234)      // value = 4
? double n = 1.234
    value = Length(n)          // value = 8
    value = Length(1.234)      // value = 4
                               // float // Numbers would be stored as the smaller data type first.
? bool n = true
    value = Length(n)      // value = 1
    value = Length(false)  // value = 1
? string n = "A""BC"
    value = Length(n)      // value = 4
                           // The string is A"BC. Two double quotation marks represent " in string
    value = Length("")     // value = 0
    value = Length("123")// value = 3
    value = Length(empty)      // value = 0
? byte[] n = {100, 200, 30}
    value = Length(n)          // value = 3
? int[] n = {}
    value = Length(n)          // value = 0
    n = {400, 500, 600}
    value = Length(n)          // value = 3
? float[] n = {1.234}
```

```
    value = Length(n)           // value = 1
?   double[] n = {1.234, 200, -100, +300}
    value = Length(n)           // value = 4
?   bool[] n = {true, false, true, true, true, true, false}
    value = Length(n)           // value = 7
?   string[] n = {"A""BC", "123", "456", "ABC"}
    value = Length(n)           // value = 4
```

4.43 Ctrl()

Change the integer or string to control characters

Syntax 1

string **Ctrl**(
int
)

Parameters

int The input integer, which follows the Big Endian format. 4 characters could be transformed at most. 0x00 will not be transformed.

Return

string The string formed by input integer (contains the control character)

Note

```
b = 0x0D0A
value = Ctrl(b)                 // value = \r\n
value = Ctrl(0x0D0A)            // value = \r\n
value = Ctrl(0x0D000A09) // value = \r\n\t   // 0x00 will not be transformed
value = Ctrl(0x0D300A09) // value = \r0\n\t // 0x30 is transformed to 0
value = Ctrl(0x00)              // value = ""
                                // empty string does not equal to NULL. For NULL, the code is Ctrl("\0")
```

Syntax 2

string **Ctrl**(
string
)

Parameters

string Input string. The following rules will be applied. For string not on the list, it will remain the same.

\0	0x00 null
\a	0x07 bell
\b	0x08 backspace
\t	0x09 horizontal tab
\r	0x0D carriage return
\v	0x0B vertical tab
\f	0x0C form feed
\n	0x0A line feed

Return

string The string formed by input integer (contains the control character)

Note

```
b = "\r\n"
value = Ctrl(b)          // value = \r\n
value = Ctrl("\r\n")     // value = \r\n
value = Ctrl("\r\n\t")   // value = \r\n\t
value = Ctrl("\r0\n\t")  // value = \r0\n\t
value = Ctrl("\0")       // value = \0      // NULL
```

Syntax 3

string **Ctrl**(
byte[]
)

Parameters

byte[] The input byte array, the transfer will start from index [0] to the end of the array. (0x00 will be transferred also)

Return

string The string formed by input integer (contains the control character)

Note

```
byte[] bb1 = {0xFF,0x55,0x31,0x32,0x33,0x00,0x35,0x36,0x0D,0x0A}
value = Ctrl(bb1)        // value = U123 56\r\n
byte[] bb2 = {}
value = Ctrl(bb2)        // value = ""
```

4.44 XOR8()

Utilize XOR 8 bits algorithm to compute the checksum

Syntax 1

byte **XOR8**(
byte[],
int,
int
)

Parameters

byte[] The input byte array

int The starting index

0..(array size-1)	Valid
<0	Invalid. Returns the initial value 0
>=array size	Invalid. Returns the initial value 0

int The number of elements to be computed.
If the number of elements <0, the calculation ends at the last element of the array
If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.

Return

byte Checksum.

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = XOR8(bb1,0,Length(bb1))   // value = 0x6F
value = XOR8(bb1,0,-1)            // value = 0x6F
value = XOR8(bb1,1,-1)            // value = 0x7F
value = XOR8(bb1,-1,-1)           // value = 0
```

Syntax 2

byte **XOR8**(
byte[],
int
)

Note

Similar to Syntax1 with computing to the last element of the array
XOR8(byte[], int) => **XOR8**(byte[], int, Length(byte[]))

Syntax 3

byte **XOR8**(
byte[]
)

Note

Similar to Syntax1 with computing all the elements of the array
XOR8(byte[]) => **XOR8**(byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
```

```
value = XOR8(bb1,0,Length(bb1))     // value = 0x6F
value = XOR8(bb1,0)                 // value = 0x6F
value = XOR8(bb1)                   // value = 0x6F
bb1 = Byte_Concat(bb1, XOR(bb1))    // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF,
                                    0x6F}
```

4.45 SUM8()

Utilize SUM 8 bits algorithm to compute the checksum

Syntax 1

byte **SUM8**(
byte[],
int,
int
)

Parameters

byte[] The input byte array

int The starting index

0..array size-1	Valid
<0	Invalid. Returns the initial value 0
>=array size	Invalid. Returns the initial value 0

int The number of elements to be computed.

If the number of elements <0, the calculation ends at the last element of the array

If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.

Return

byte Checksum.

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM8(bb1,0,Length(bb1))   // value = 0x6D
value = SUM8(bb1,0,-1)            // value = 0x6D
value = SUM8(bb1,1,-1)            // value = 0x5D
value = SUM8(bb1,-1,-1)           // value = 0
```

Syntax 2

byte **SUM8**(
byte[],
int
)

Note

Similar to Syntax1 with computing to the last element of the array

SUM8(byte[], int) => **SUM8**(byte[], int, Length(byte[]))

Syntax 3

byte **SUM8**(
byte[]
)

Note

Similar to Syntax1 with computing all the elements of the array

SUM8(byte[]) => **SUM8**(byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM8(bb1,0,Length(bb1))   // value = 0x6D
value = SUM8(bb1,0)               // value = 0x6D
```

```
value = SUM8(bb1)                    // value = 0x6D
bb1 = Byte_Concat(bb1, SUM8(bb1))    // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF,
                                     0x6D}
```

4.46 SUM16()

Utilize SUM 16 bits algorithm to compute the checksum

Syntax 1

byte[] **SUM16**(
byte[],
int,
int
)

Parameters

byte[]	The input byte array	
int	The starting index	
	0..array size-1	Valid
	<0	Invalid. Returns the initial value 0
	>=array size	Invalid. Returns the initial value 0
int	The number of elements to be computed.	
	If the number of elements <0, the calculation ends at the last element of the array	
	If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.	

Return

byte[] Checksum. The length is 16bits 2 bytes (The Checksum follows Big Endian)

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM16(bb1,0,Length(bb1)) // value = {0x04, 0x6D}
value = SUM16(bb1,0,-1)          // value = {0x04, 0x6D}
value = SUM16(bb1,1,-1)          // value = {0x04, 0x5D}
value = SUM16(bb1,-1,-1)         // value = {0x00, 0x00}
```

Syntax 2

byte[] **SUM16**(
byte[],
int
)

Note

Similar to Syntax1 with computing to the last element of the array
SUM16(byte[], int) => **SUM16**(byte[], int, Length(byte[]))

Syntax 3

byte[] **SUM16**(
byte[]
)

Note

Similar to Syntax1 with computing all the elements of the array
SUM16(byte[]) => **SUM16**(byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM16(bb1,0,Length(bb1)) // value = {0x04, 0x6D}
```

```
value = SUM16(bb1,0)                    // value = {0x04, 0x6D}
value = SUM16(bb1)                      // value = {0x04, 0x6D}
bb1 = Byte_Concat(bb1, SUM16(bb1))      // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF,
                                        0x04, 0x6D}
```

4.47 SUM32()

Utilize SUM 32 bits algorithm to compute the checksum

Syntax 1

byte[] **SUM32**(
byte[],
int,
int
)

Parameters

byte[]	The input byte array	
int	The starting index	
	0..array size-1	Valid
	<0	Invalid. Returns the initial value 0
	>=array size	Invalid. Returns the initial value 0
int	The number of elements to be computed.	
	If the number of elements <0, the calculation ends at the last element of the array	
	If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.	

Return

byte[] Checksum. The length is 32bits 4 bytes (The Checksum follows Big Endian)

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM32(bb1,0,Length(bb1)) // value = {0x00, 0x00, 0x04, 0x6D}
value = SUM32(bb1,0,-1)          // value = {0x00, 0x00, 0x04, 0x6D}
value = SUM32(bb1,1,-1)          // value = {0x00, 0x00, 0x04, 0x5D}
value = SUM32(bb1,-1,-1)         // value = {0x00, 0x00, 0x00, 0x00}
```

Syntax 2

byte[] **SUM32**(
byte[],
int
)

Note

Similar to Syntax1 with computing to the last element of the array
SUM32(byte[], int) => **SUM32**(byte[], int, Length(byte[]))

Syntax 3

byte[] **SUM32**(
byte[]
)

Note

Similar to Syntax1 with computing all the elements of the array
SUM32(byte[]) => **SUM32**(byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = SUM32(bb1,0,Length(bb1)) // value = {0x00, 0x00, 0x04, 0x6D}
```

```
value = SUM32(bb1,0)                    // value = {0x00, 0x00, 0x04, 0x6D}
value = SUM32(bb1)                      // value = {0x00, 0x00, 0x04, 0x6D}
bb1 = Byte_Concat(bb1, SUM32(bb1))      // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF,
                                        0x00, 0x00, 0x04, 0x6D}
```

4.48 CRC16()

Utilize CRC 16 bits algorithm to compute the checksum

Syntax 1

```
byte[] CRC16(
    int,
    byte[],
    int,
    int
)
```

Parameters

int	CRC16 algorithm	
	0 CRC16	// initial value 0x0000 // Polynomial 0xA001
	1 CRC16 (Modbus)	// initial value 0xFFFF// Polynomial 0xA001
	2 CRC16 (Sick)	// initial value 0x0000 // Polynomial 0x8005
	3 CRC16-CCITT (0x1D0F)	// initial value 0x1D0F// Polynomial 0x1021
	4 CRC16-CCITT (0xFFFF)	// initial value 0xFFFF// Polynomial 0x1021
	5 CRC16-CCITT (XModem)	// initial value 0x0000 // Polynomial 0x1021
	6 CRC16-CCITT (Kermit)	// initial value 0x0000 // Polynomial 0x8408
	7 CRC16 Schunk Gripper	// initial value 0xFFFF// Polynomial 0x1021
byte[]	The input byte array	
int	The starting index	
	0..array size-1	Valid
	<0	Invalid. Returns the initial value
	>=array size	Invalid. Returns the initial value
int	The number of elements to be computed.	
	If the number of elements <0, the calculation ends at the last element of the array	
	If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.	

Return

byte[]	Checksum. The length is 16bits 2 bytes (The checksum follows Big Endian)

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = CRC16(0, bb1,0,Length(bb1))      // value = {0x2D, 0xD4}
value = CRC16(0, bb1,0,-1)               // value = {0x2D, 0xD4}
value = CRC16(0, bb1,1,-1)               // value = {0xEC, 0xC5}
value = CRC16(0, bb1,-1,-1)              // value = {0x00, 0x00}
value = CRC16(3, bb1,0,Length(bb1))      // value = {0x42, 0x12}
value = CRC16(4, bb1,0,Length(bb1))      // value = {0xAB, 0xAE}
```

Syntax 2

```
byte[] CRC16(
    int,
    byte[],
    int
)
```

Note

Similar to Syntax1 with computing to the last element of the array

CRC16(int, byte[], int) => **CRC16**(int, byte[], int, Length(byte[]))

Syntax 3

```
byte[] CRC16(
    int,
    byte[]
)
```

Note

Similar to Syntax1 with computing all the elements of the array

CRC16(int, byte[]) => **CRC16**(int, byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = CRC16(0, bb1,0,Length(bb1))        // value = {0x2D, 0xD4}
value = CRC16(0, bb1,0)                    // value = {0x2D, 0xD4}
value = CRC16(0, bb1)                      // value = {0x2D, 0xD4}
bb1 = Byte_Concat(bb1, CRC16(0, bb1))      // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF,
                                           0x2D, 0xD4}
```

Syntax 4

```
byte[] CRC16(
    byte[],
    int,
    int
)
```

Note

Similar to Syntax1 with CRC16 algorithm as 0 CRC16

CRC16(byte[], int, int) => **CRC16**(0, byte[], int, int)

Syntax 5

```
byte[] CRC16(
    byte[],
    int
)
```

Note

Similar to Syntax1 with CRC16 algorithm as 0 CRC16 and computing to the last element of the array

CRC16(byte[], int) => **CRC16**(0, byte[], int, Length(byte[]))

Syntax 6

```
byte[] CRC16(
    byte[]
)
```

Note

Similar to Syntax1 with CRC16 algorithm as 0 CRC16 and computing all the elements of the array

CRC16(byte[]) => **CRC16**(0, byte[], 0, Length(byte[]))

4.49 CRC32()

Utilize CRC 32 bits algorithm to compute the checksum

Syntax 1

byte[] **CRC32**(
byte[],
int,
int
)

Parameters

byte[] The input byte array

int The starting index

0..array size-1	Valid
<0	Invalid. Returns the initial value 0
>=array size	Invalid. Returns the initial value 0

int The number of elements to be computed.
If the number of elements <0, the calculation ends at the last element of the array
If the sum of starting index and number of element exceeds the array size, the calculation ends at the last element of the array.

Return

byte[] Checksum. The checksum length is 32bits 4 bytes (The checksum follows Big Endian)

Note

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}

value = CRC32(bb1,0,Length(bb1)) // value = {0x43, 0xD5, 0xB9, 0xF8}
value = CRC32(bb1,0,-1)          // value = {0x43, 0xD5, 0xB9, 0xF8}
value = CRC32(bb1,1,-1)          // value = {0x08, 0xA5, 0x5B, 0xEB}
value = CRC32(bb1,-1,-1)         // value = {0x00, 0x00, 0x00, 0x00}
```

Syntax 2

byte[] **CRC32**(
byte[],
int
)

Note

Similar to Syntax1 with computing to the last element of the array
CRC32(byte[], int) => **CRC32**(byte[], int, Length(byte[]))

Syntax 3

byte[] **CRC32**(
byte[]
)

Note

Similar to Syntax1 with computing all the elements of the array
CRC32(byte[]) => **CRC32**(byte[], 0, Length(byte[]))

```
byte[] bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF}
value = CRC32(bb1,0,Length(bb1))        // value = {0x43, 0xD5, 0xB9, 0xF8}
value = CRC32(bb1,0)                    // value = {0x43, 0xD5, 0xB9, 0xF8}
value = CRC32(bb1)                      // value = {0x43, 0xD5, 0xB9, 0xF8}
bb1 = Byte_Concat(bb1, CRC32(bb1))
        // bb1 = {0x10, 0x20, 0x50, 0xF0, 0xFF, 0xFF, 0xFF, 0x43, 0xD5, 0xB9, 0xF8}
```

4.50 ListenPacket()

Pack the string contents as the compatible protocol for the Listen Node (External Script Control Mode)

Syntax 1

string **ListenPacket**(
    string,
    string
)

Parameters

string	User defined Header. For empty string, Default string "TMSCT" will be applied
string	The data section in Listen Node communication format

Return

string	Packed data (Including header, data length and check sum)

Note

```
string var_data1 = "1, var_i++"
string var_data2 = "Hello World"

value = ListenPacket("TMSCT", var_data1)      // $TMSCT,9,1,var_i++,*06\r\n
value = ListenPacket("", var_data2)           // $TMSCT,11,Hello World,*51\r\n
                                              // Error for TMSCT
value = ListenPacket("", "2,Techman Robot")   // $TMSCT,15,2,Techman Robot,*57\r\n
value = ListenPacket("TMSTA", var_data2)      // $TMSTA,11,Hello World,*53\r\n
                                              // Error for TMSTA
value = ListenPacket("TMSTA", "00")           // $TMSTA,2,00,*41\r\n
```

Syntax 2

string **ListenPacket**(
    string
)

Parameters

string	The data section in Listen Node communication format (With TMSCT header)

Return

string	Packed data (Including header, data length and check sum)

Note

```
string var_data1 = "1,var_counter++"          // ScriptID, ScriptLanguage
value = ListenPacket(var_data1)               // $TMSCT,15,1, var_counter++,*26\r\n
```

4.51 ListenSend()

Send TMSTA, the communication protocol of Listen node, to the client devices connected to the Listen Server currently.

Syntax1

int **ListenSend**(
    string,
    int,
    ?
)

Parameters

string	Target IP filtering such as 127.0.0.1 meaning to send to all client devices connecting from 127.0.0.1.
int	TMSTA SubCmd numbering for sending self-defined data message only 90 .. 99
?	The value to send. Available types: byte, int, float, double, bool, and string. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.

Return

int	Return the result	
	0	sent successfully
	-1	error. Listen Server is not starting.
	-2	error. SubCmd must be between 90 and 99.

Syntax2

int **ListenSend**(
    int,
    ?
)

Parameters

int	TMSTA SubCmd numbering for sending self-defined data message only 90 .. 99
?	The value to send. Available types: byte, int, float, double, bool, and string. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.

Return

int	Return the result	
	0	sent successfully
	-1	error. Listen Server is not starting.
	-2	error. SubCmd must be between 90 and 99.

Note

No target IP filtering will result in sending data messages to all connected client devices.

Note

```
string ip = "127.0.0.1"

byte b = 100
value = ListenSend(ip, 10, b)
    // send 0x64 to ipfilter "127.0.0.1"      // value = -2      // SubCmd must be between 90 and 99.
```

```
value = ListenSend(ip, 90, b)
    // send 0x64 to ipfilter "127.0.0.1"      // value = -1      // Supposedly Listen Server is not starting.
value = ListenSend(ip, 90, b)
    // send 0x64 to ipfilter "127.0.0.1"      // value = 0       // sent successfully
    // IP filtering 127.0.0.1 and send to the devices connected to Listen Server via the IP.
    // $TMSTA,4,90,d,*06                      // The value of 100 is conversed to 0x64.
value = ListenSend(ip, 90, 123456)
    // send 0x40 0xE2 0x01 0x00 to ipfilter "127.0.0.1"
    // $TMSTA,7,90,@□ ,*C2
    // The value of 123456 is conversed to 0x40 0xE2 0x01 0x00 (int, Little Endian)
value = ListenSend(90, "123.456")
    // send 0x31 0x32 0x33 0x2E 0x34 0x35 0x36
    // No target IP filtering will result in sending data messages to all connected client devices.
    // $TMSTA,10,90,123.456,*7E
    // The value of "123.456" is conversed to 0x31 0x32 0x33 0x2E 0x34 0x35 0x36 (string, UTF8).
byte[] bb = {100, 200}
value = ListenSend(90, bb)
    // send 0x64 0xC8
    // $TMSTA,5,90,d□,*CF    // The value of {100, 200} is conversed to 0x64 0xC8
string[] ss = {"T", "M", "達明機器人" }
value = ListenSend(90, ss)
    // send 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA
    0xBA
    // $TMSTA,20,90,TM達明機器人,*A1
```

4.52 VarSync()

Send the Variable object to TMmanager (Robot Management System)
* When performing this function, the flow will not go on until the object is sent out successfully or the maximum retry times is reached.

Syntax 1

```
int VarSync(
    int,
    int,
    ?
)
```

Parameters

int	The maximum times to retry	
	<= 0	Keep retrying as error occurred.
int	The time duration between two retries (millisecond)	
	< 0	Invalid time duration. The default value, 1000ms, will be applied
?	The string or string array. The name of variables to be sent. Multiple items can be listed. If there are indefinite variables, they will be not be sent; other definite variables will be sent. * The item is the name of the variable, not what the variable equals such that i goes with "i". * If the variable is listed, the value of the variable will be used to send the matched object.	

Return

int	Sending times	
	> 0	Send success. The return value returns the sending times
	0	Send failed
	-1	TM Manager function is not enabled
	-9	Invalid Parameters

Note

```
string var_s = "ABC"
string var_s1 = " var_s"
string[] var_ss = {"ABC", " var_s", " var_s1"}
value = VarSync(1, 1000, " var_s") // Send var_s variable object
value = VarSync(2, 2000, var_s)    // Send ABC variable object (Because the value of var_s is "ABC")
value = VarSync(3, 2000, var_ss)   // Send ABC, var_s, var_s1 variable object (From the value of ss string array)
value = VarSync(3, 2000, " var_ss")      // Send var_ss variable object
value = VarSync(4, 2000, " var_ss", " var_s1", "ABC")// Send var_ss, var_s1, ABC variable object
```

Syntax 2

```
int VarSync(
    int,
    ?
)
```

Note

Same as Syntax 1 with the time between two retries defaults to 1000 ms.
VarSync(int, ?) => **VarSync**(int, 1000, ?)

Syntax 3

int **VarSync**(
    ?
)

Note

Same as Syntax 1 with the time between two retries defaults to 1000 ms without limit of times to retry
VarSync(?) => **VarSync**(0, 1000, ?)

5. General Functions (Script)
5.1 Exit()

Stop the project running.

Syntax 1

void **Exit**(
bool,
int
)

Parameter

bool	Whether to wait for the end of the motion command to stop the project	
	true	Wait (default)
	false	No wait
int	Ending code	
	> 0	Execute the closestop funciton.
	== 0	Evaluate if the project errs. (default)
	< 0	Execute the errorstop funciton.

Return

void	No return

Syntax 2

void **Exit**(
bool
)

Parameter

bool	Whether to wait for the end of the motion command to stop the project	
	true	Wait (default)
	false	No wait

Note

Same as syntax 1. It defaults 0 to the ending code.

Syntax 3

void **Exit**(
)

Parameter

void	No input

Note

Same as syntax 1. It defaults true to whether to wait for the end of the motion command to stop the project and 0 to the ending code.

Syntax 4

void **Exit**(
int
)

Parameter

int Ending code.

> 0 Execute the closestop funciton.

== 0 Same as syntax 1. Evaluates if the project errs.

< 0 Execute the errorstop funciton.

Note

Same as syntax 1. It defaults true to whether to wait for the end of the motion command to stop the project.

Exit()

// Wait for the end of the motion command, stop the project running, and assess if errors occurred.

// Run the closestop function next when there is no error.

// Run the errorstop function next when there is an error.

Exit(false) // Wait not for the end of the motion command not, stop the project running shortly, and assess if errors occurred.

Exit(false, 1) // Wait not for the end of the motion command not, stop the project running shortly, and run the closestop function.

Exit(1) // Wait for the end of the motion command, stop the project running, and run the closestop function.

Exit(0) // Wait for the end of the motion command, stop the project running, and assess if errors occurred.

Exit(-1) // Wait for the end of the motion command, stop the project running, and run the errorstop function.

5.2 Pause()

Pause the project and the motion of the robot other than non-paused threads and external script processes. Use Resume() or press the Play button on the robot stick to resume.

Syntax 1

bool **Pause**(
)

Parameter

void No parameter

Return

bool True Command accepted； False Command rejected

Note

Pause()

5.3 Resume()

Resume the project and the motion of the robot.

Syntax 1

bool **Resume**(
)

Parameter

void No parameter

Return

bool True Command accepted； False Command rejected

Note

Resume()

5.4 WaitFor()

The loop wait condition stands or time out on waiting.

Syntax 1

bool **WaitFor**(
    bool,
    int
)

Parameter

bool	The loop wait condition. It can be true/false or a statement returns the bool value.	
int	wait time (millisecond)	
	< 0	wait indefinitely
	>= 0	time to wait

Return

Bool	Return True for the loop wait condition stands and False for time out on waiting.

Note

```
int i = 0
bool flag = WaitFor(i++ > 100, 1000)
// The loop executes i++ and judges whether it is larger than 100. It exits the loop at once if the condition satisfies (flag = true) or it is timeout after 1000ms (flag = false).
```

Syntax 2

bool **WaitFor**(
    int
)

Parameter

int	wait time (millisecond)	
	< 0	invalid
	>= 0	time to wait

Return

bool	Return True for the wait time stands and False for not. (Interrupted by the project stop)

Note

```
WaitFor(100)            // Timeout after 100ms of waiting.
```

5.5 Sleep()

Stop the thread in the time specified. Same as WaitFor(int).

Syntax 1

bool **Sleep**(
    int
)

Parameter

int	wait time (millisecond)	
	< 0	invalid
	>= 0	time to wait

Return

bool	Return True for the wait time stands and False for not. (Interrupted by the project stop)

Note

```
Sleep(100)        // Timeout after 100ms of waiting.
```

5.6 Display()

Display contents on the TMflow dashboard.

Syntax 1

bool **Display**(
string,
string,
string,
string
)

Parameter

string	Headline text color	
	"Red"	Set headline background color to red.
	"Green"	Set headline background color to green.
	"Blue"	Set headline background color to blue.
	"Yellow"	Set headline background color to yellow.
	"Black"	Set headline background color to black.
	"White"	Set headline background color to white.
	"Gray"	Set headline background color.to gray.
string	Headline background color	
	"Red"	Set headline text color to red.
	"Green"	Set headline text color to green.
	"Blue"	Set headline text color to blue.
	"Yellow"	Set headline text color to yellow.
	"Black"	Set headline text color to black.
	"White"	Set headline text color to white.
	"Gray"	Set headline text color to gray.
string	Headline text	
string	Text	

Return

bool Return True for set successfully and False for unsuccessfully.

Note

Display("Yellow", "Green", "Gripper Initial Finish", "Force = 30N") // Output the headline of Gripper Initial Finish with the text of Force = 30N to the TMflow dashboard and set headline text color to yellow and headline background color to green.

Syntax 2

bool **Display**(
string,
string
)

Parameter

string	Headline text
string	Text

Note

Same as Syntax 1. It sets headline text color to black and headline background color to white by default.

Syntax 3

bool **Display**(
    string
)

Parameter

string	Text

Note

Same as Syntax 1. It sets headline text color to black and headline background color to white by default. The headline text is an empty string.

5.7 ExecText()

Check and execute the string content input, which must comply with the TMscript definition.

Syntax 1

bool **ExecText**(
    string
)

Parameters

string	The string content to execute	
Return		
bool	Returns the result of checking the string content	
	True	Check passed. Will proceed to execute the string content
	False	Check failed. The string content is not executed.

Note

```
bool result = false

// Display(“Hello World”) is the string parameter passed to the ExecText() function, so “Hello World” must be enclosed in double quotes.
result = ExecText("Display(""Hello World"")")   // The result = True will display Hello World.

// Users can use multi-line input \ to combine multiple lines of string content, making it easier to read and edit.
// Combine Display("This is Line1")
        Pause()
        Display("This is Line3")
// into a string str1
string str1 = "Display(""This is Line1"")" + newline + \
              "Pause()" + newline + \
              "Display(""This is Line3"")"
result = ExecText(str1)       // Display “This is Line1”, pause, then display “This is Line3” after resuming.
```

5.8 ExecFile()

Check and execute the file path input, where the string content read from the file must comply with the TMscript definition.

Syntax 1

bool **ExecFile**(
    string
)

Parameters

string	The file path to execute

Return

bool	Returns the result of checking the file path.
True	Check passed. Will proceed to execute the file content
False	Check failed. The file content is not executed.

Note

*Users can refer to the File Functions chapter for File paths.

.\TextFiles\ExecTrue.txt

```
1|  // Use PTP to move to a specific point.
2|  PTP("JPP", {30,0,90,0,90,0}, 10, 500, 100, true)
3|  Display("This is Test ExecFile")
```

.\TextFiles\ExecFalse.txt

```
1|  // This is a incorrect syntax
2|  Display123("This is a wrong text file")
```

```
bool result = false
bool existed = File_Exists(".\TextFiles\ExecTrue.txt")    // First, verify that the file exists.
if (existed)
{
    // The ExecTrue.txt file contains correct syntax, so the system sets result = true and executes its contents.
    result = ExecFile(".\TextFiles\ExecTrue.txt")
}
// The ExecTrue.txt file contains incorrect syntax, so the system sets result = false and does not execute its contents.
result = ExecFile("ExecFalse.txt")
// If the ExecTrue11.txt file does not exist, executing this line will cause an error and halt the project.
ExecFile("ExecTrue11.txt")
```

5.9 RedirectToProject()

Stop the currently running project and proceed to execute the specified project.

Syntax 1

void **RedirectToProject**(
    string
)

Parameters

string	The project name

Return

void	No return

Note

```
RedirectToProject("Project2")        // Stop the current project to run the “Project2” project.
```

- If the specified project doesn't exist, the system reports an error and stops execution.
- Functions following RedirectToProject() will not execute, such as

```
Display("Project1 has finished!")
RedirectToProject("Project2")        // Stop the current project and continue running the "Project2" project.
Display("Project2!")                 // The system skips this line, stopping its execution.
```

- However, syntax checking will still occur for code following RedirectToProject().

```
RedirectToProject("Project2")        // Stop the current project and continue running the "Project2" project.
Display(100 / 0)                     // Syntax check detected a division-by-zero error.
```

- When this function targets a Flow project, it skips the settings in the Start node of that project, preventing their execution.
- If used within a Listen node, the connection to the Listen node will be interrupted due to the termination of that project.

6. Math Functions

6.1 abs()

Return the absolute value of the designate number

Syntax 1

int **abs**(
    int
)

Parameter

int	Input number in integer

Return

int	Return the absolute value of the input number in integer

Note

```
int i = 10
value = abs(i)      // 10
i = -10
value = abs(i)      // 10
```

Syntax 2

float **abs**(
    float
)

Parameter

float	Input number in float

Return

float	Return the absolute value of the input number in float

Note

```
float f = 10.1
value = abs(f)      // 10.1
f = -10.1
value = abs(f)      // 10.1
```

Syntax 3

double **abs**(
    double
)

Parameter

double	Input number in double

Return

double	Return the absolute value of the input number in double

Note

```
double d = 10.8
value = abs(d)      // 10.8
d = -10.8
value = abs(d)      // 10.8
```

6.2 pow()

Return the power of the designate base and exponent

Syntax 1

```
int pow(
    int,
    double
)
```

Parameter

int	Input base in integer
double	Exponent

Return

int	Return the power in integer

Syntax 2

```
float pow(
    float,
    double
)
```

Parameter

float	Input base in float
double	Exponent

Return

float	Return the power in float

Syntax 3

```
double pow(
    double,
    double
)
```

Parameter

double	Input base in double
double	Exponent

Return

double	Return the power in double

Note

```
? int b = 100
    value = pow(b, 2)      // 10000
    value = pow(b, -2)     // 0       // 0.0001, but int type
    value = pow(b, 0.1)    // 1       // 1.5848932, but int type
    value = pow(b, 2.1)    // 15848   // 15848.932, but int type
    value = pow(b, -2.1)   // 0       // 6.309574E-05, but int type
? float b = -100
    value = pow(b, 2)      // 10000
    value = pow(b, -2)     // 0.0001
    value = pow(b, 0.2)    // Error // NaN
    value = pow(b, 2.2)    // Error // NaN
```

```
value = pow(b, -2.2)   // Error // NaN

? double b = 100
value = pow(b, 2)      // 10000
value = pow(b, -2)     // 0.0001
value = pow(b, 0.31)   // 4.168694
value = pow(b, 2.31)   // 41686.938
value = pow(b, -2.31)  // 2.3988328E-05
```

6.3 sqrt()

Return the square root of the designate number

Syntax 1

float **sqrt**(
float
)

Parameter

float Input number in float

Return

float Return the square root in float

Syntax 2

double **sqrt**(
double
)

Parameter

double Input number in double

Return

double Return the square root in double

Note

```
value = sqrt(100)          // 10
value = sqrt(100.1234)     // 10.006168
value = sqrt(0.1234)       // 0.35128337
value = sqrt(-100)         // Error // NaN
value = sqrt(-100.1234)    // Error // NaN
value = sqrt(-0.1234)      // Error // NaN
```

6.4 ceil()

Return a number rounded upward to its nearest integer.

Syntax 1

```
float ceil(
    float
)
```

Parameter

float input number in float

Return

float Return a number in float rounded upward to its nearest integer

Syntax 2

```
double ceil(
    double
)
```

Parameter

double input number in double

Return

double Return a number in double rounded upward to its nearest integer

Note

```
value = ceil(100)          // 100
value = ceil(100.1234)     // 101
value = ceil(0.1234)       // 1
value = ceil(-100)         // -100
value = ceil(-100.1234)    // -100
value = ceil(-0.1234)      // 0
```

6.5 floor()

Return a number rounded downward to its nearest integer.

Syntax 1

float **floor**(
    float
)

Parameter

float input number in float

Return

float Return a number in float rounded downward to its nearest integer

Syntax 2

double **floor**(
    double
)

Parameter

double input number in double

Return

double Return a number in double rounded downward to its nearest integer

Note

```
value = floor(100)          // 100
value = floor(100.1234)     // 100
value = floor(0.1234)       // 0
value = floor(-100)         // -100
value = floor(-100.1234)    // -101
value = floor(-0.1234)      // -1
```

6.6 round()

Return a number rounded to its nearest integer.

Syntax 1

float **round**(
    float,
    int
)

Parameter

float	input number in float	
int	digits after the returned decimal point (0 by default meaning the number is rounded to integer)	
	0 .. 15	valid values
	< 0	value invalid, will use 0 by default
	> 15	value invalid, will use 0 by default

Return

float Return a number in float rounded to its nearest integer.

Syntax 2

float **round**(
    float
)

Note

Same as syntax 1. Obtain 0 digit after the decimal point by default.
round(float) => **round**(float, 0)

Syntax 3

double **round**(
    double,
    int
)

Parameter

double	input number in double	
int	digits after the returned decimal point (0 by default meaning the number is rounded to integer)	
	0 .. 15	valid values
	< 0	value invalid, will use 0 by default
	> 15	value invalid, will use 0 by default

Return

double Return a number in double rounded to its nearest integer.

Syntax 4

double **round**(
    double
)

Note

Same as syntax 3. Obtain 0 digit after the decimal point by default.

round(double) => **round**(double, 0)

```
value = round(100)              // 100
value = round(100.456)          // 100
value = round(0.567)            // 1
value = round(-100)             // -100
value = round(-100.456)         // -100
value = round(-0.567)           // -1
value = round(100.345, 1)       // 100.3
value = round(100.345, 2)       // 100.35
value = round(-100.345, 1)      // -100.3
value = round(-100.345, 2)      // -100.35
value = round(-100.345, 16)     // -100
```

6.7 random()

Return a random value in float between 0 and 1 or in an integer between the lower bound and the upper bound.

Syntax 1

float **random**(
)

Parameter

void	No parameter

Return

float	Return a random value in float, where the value is greater than or equal to 0 and less than 1 (0 <= RND < 1).

Note

```
value = random()      // 0.9473762
value = random()      // 0.7764986
value = random()      // 0.9911129
```

Syntax 2

int **random**(
int
)

Parameter

int	The upper bound of the specified random value

Return

int	Return a random value in an integer, where the value is greater than or equal to 0 and less than the upper bound (0 <= RND < MAX).

Note

```
value = random(10)      // 8
value = random(10)      // 1
value = random(10)      // 5
value = random(-10)     // 0   // The value of the upper bound must be larger than 0.
```

Syntax 3

int **random**(
int,
int
)

Parameter

int	The lower bound of the random value
int	The upper bound of the random value must be larger than the lower bound, or it will return the value of the lower bound in integer.

Return

int	Return a random value in an integer between the lower bound and the upper bound (MIN <= RND < MAX).

Note

```
value = random(5, 10)      // 8
```

```
value = random(5, 10)    // 8
value = random(5, 10)    // 6
value = random(5, -1)    // 5    // The upper bound is smaller than the lower bound. Returned the
                                value of the lower bound in integer.
```

6.8 sum()

Return the sum of the given numbers or the array of numbers.

Syntax 1

int **sum**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, byte[], or int[] calculate the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

int	Return the sum, in the integer type, of the given numbers.

Syntax 2

double **sum**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of float, double, float[], or double[] calculate the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the sum, in the double type, of the given numbers.

Note

```
int sum1 = sum(1,2,3,4,5)                                  // 15
int sum2 = sum(1,2,3,4,{5,6,7,8})                          // 36
int sum3 = sum(1,2,3,4,{5,6,7,8},1.2)                      // 37      // due to putting the int type
double sum4 = sum(1,2,3,4,{5,6,7,8},1.2)                   // 37.2
double sum5 = sum(1,2,3,4,{5,6,7,8},9.2)                   // 45.2
double sum6 = sum(1,2,3,4,{5,6,7,8},9.2,sum5,{1.2,3.4})    // 95
```

6.9 average()

Return the average of the given numbers or the array of numbers.

Syntax 1

double **average**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, float, double, byte[], int[], float[], or double[] calculate the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the average, in the double type, of the given numbers.

Note

```
double avg1 = average(1,2,3,4,5)                          // 3
double avg2 = average(1,2,3,4,{5,6,7,8},9.2)              // 5.02222222222222
double avg3 = average(1,2,3,4,sum({5,6,7,8}),9.2)         // 7.53333333333333
double avg4 = average(1,2,3,4,{5,6,7,8},9.2,{1.2,3.4}) // 4.52727272727273
```

6.10 stdevp()

Return the standard deviation $\sigma = \sqrt{\sum \left(X - \frac{\sum X}{N}\right)^2 / N}$ based on the entire population of the given numbers or the array of numbers.

Syntax 1

double **stdevp**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, float, double, byte[], int[], float[], or double[]
	calculate the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the standard deviation, in the double type, of the given numbers.

Note

```
double stdp1 = stdevp(1,2,3,4,5)                        // 1.4142135623731
double stdp2 = stdevp(1,2,3,4,{5,6,7,8},9.2)            // 2.61694384000276
double stdp3 = stdevp(1,2,3,4,sum({5,6,7,8}),9.2)       // 8.66153694341958
double stdp4 = stdevp(1,2,3,4,{5,6,7,8},9.2,{1.2,3.4}) // 2.63165724111457
```

6.11 stdevs()

Return the standard deviation $s = \sqrt{\sum \left(X - \frac{\sum X}{N}\right)^2 / (N-1)}$ based on a sample of the given numbers or the array of numbers.

Syntax 1

double **stdevs**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, float, double, byte[], int[], float[], or double[]
	calculate the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the standard deviation, in the double type, of the given numbers.

Note

```
double stds1 = stdevs(1,2,3,4,5)                    // 1.58113883008419
double stds2 = stdevs(1,2,3,4,{5,6,7,8},9.2)        // 2.77568810287547
double stds3 = stdevs(1,2,3,4,sum({5,6,7,8}),9.2)   // 9.4882383331505
double stds4 = stdevs(1,2,3,4,{5,6,7,8},9.2,{1.2,3.4}) // 2.76010539983201
```

6.12 min()

Return the minimum of the given numbers or the array of numbers.

Syntax 1

int **min**(
?,
...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, byte[], or int[] compare the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

int	Return the minimum, in the integer type, of the given numbers.

Syntax 2

double **min**(
?,
...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of float, double, float[], or double[] compare the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the minimum, in the double type, of the given numbers.

Note

```
int min1 = min(1,2,3)                          // 1
int min2 = min(1,2,3,{-4,-5.3,6.2},1.2)        // -5      // due to putting the int type
double min3 = min(1,2,3,{-4,-5.3,6.2},1.2)     // -5.3
double min4 = min(1,2,3,{-0.2,-0.1,0.1},9.2)   // -0.2
```

6.13 max()

Return the maximum of the given numbers or the array of numbers.

Syntax 1

int **max**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of byte, int, byte[], or int[] compare the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

int	Return the maximum, in the integer type, of the given numbers.

Syntax 2

double **max**(
    ?,
    ...
)

Parameter *(variable parameter amount)*

?	input value, can be in the type of float, double, float[], or double[] compare the value of each parameter or each element in the array. It returns an error and stops if it comes with a non-numeric type.

Return

double	Return the maximum, in the double type, of the given numbers.

Note

```
int max1 = max(1,2,3)                                  // 3
int max2 = max(1,2,3,{-4,-5.3,6.2},1.2)                // 6      // due to putting the int type
double max3 = max(1,2,3,{-4,-5.3,6.2},1.2)             // 6.2
double max4 = max(1,2,3,{-0.2,-0.1,0.1},9.2)           // 9.2
```

6.14 d2r()

Convert the value of degree to radian

Syntax 1

float **d2r**(
float
)

Parameter

float Input the value of degree in float

Return

float Return the value of radian in float

Syntax 2

double **d2r**(
double
)

Parameter

double Input the value of degree in double

Return

double Return the value of radian in double

Note

```
value = d2r(1)          // 0.017453292
```

6.15 r2d()

Convert the value of degree to radian to degree

Syntax 1

float **r2d**(
float
)

Parameter

float Input the value of radian in float

Return

float Return the value of degree in float

Syntax 2

double **r2d**(
double
)

Parameter

double Input the value of radian in double

Return

double Return the value of degree in double

Note

value = **r2d**(1) // 57.29578

6.16 sin()

Return the sine of the input value of degree

Syntax 1

float **sin**(
float
)

Parameter

float Input the value of degree in float

Return

float Return the sine of the input value of degree in float

Syntax 2

double **sin**(
double
)

Parameter

double Input the value of degree in double

Return

double Return the sine of the input value of degree in double

Note

```
value = sin(0)      // 0
value = sin(15)     // 0.25881904
value = sin(30)     // 0.5
value = sin(60)     // 0.8660254
value = sin(90)     // 1
```

6.17 cos()

Return the cosine of the input value of degree

Syntax 1

float **cos**(
float
)

Parameter

float Input the value of degree in float

Return

float Return the cosine of the input value of degree in float

Syntax 2

double **cos**(
double
)

Parameter

double Input the value of degree in double

Return

double Return the cosine of the input value of degree in double

Note

```
value = cos(0)      // 1
value = cos(15)     // 0.9659258
value = cos(30)     // 0.8660254
value = cos(45)     // 0.70710677
value = cos(60)     // 0.5
```

6.18 tan()

Return the tangent of the input value of degree

Syntax 1

float **tan**(
float
)

Parameter

float Input the value of degree in float

Return

float Return the tangent of the input value of degree in float

Syntax 2

double **tan**(
double
)

Parameter

double Input the value of degree in double

Return

double Return the tangent of the input value of degree in double

Note

```
value = tan(0)      // 0
value = tan(15)     // 0.2679492
value = tan(30)     // 0.57735026
value = tan(45)     // 1
value = tan(60)     // 1.7320508
```

6.19 asin()

Return the arcsine of the input value in degree

Syntax 1

float **asin**(
    float
)

Parameter

float	Input the sine value in float between -1 and 1

Return

float	Return the arcsine of the input value of degree in float

Syntax 2

double **asin**(
    double
)

Parameter

double	Input the sine value in double between -1 and 1

Return

double	Return the arcsine of the input value of degree in double

Note

```
value = asin(0)              // 0
value = asin(0.258819)       // 14.999998
value = asin(0.5)            // 30
value = asin(0.8660254)      // 60
value = asin(1)              // 90

value = asin(sin(15))        // 15
value = asin(sin(60))        // 60
```

6.20 acos()

Return the arccosine of the input value in degree

Syntax 1

float **acos**(
    float
)

Parameter

float	Input the cosine value in float between -1 and 1

Return

float	Return the degree value in float

Syntax 2

double **acos**(
    double
)

Parameter

double	Input the cosine value in double between -1 and 1

Return

double	Return the degree value in double

Note

```
value = acos(1)              // 0
value = acos(0.9659258)      // 15.000003
value = acos(0.8660254)      // 30.000002
value = acos(0.7071068)      // 44.999996
value = acos(0.5)            // 60

value = acos(cos(15))        // 15.000003
value = acos(cos(30))        // 30.000002
value = acos(cos(45))        // 45

value = acos(cos((double)15)) // 14.999999999999996
value = acos(cos((double)30)) // 29.999999999999993
```

6.21 atan()

Return the arctangent of the input value in degree

Syntax 1

float **atan**(
    float
)

Parameter

float	Input the arctangent value in float

Return

float	Return the degree value in float

Syntax 2

double **atan**(
    double
)

Parameter

double	Input the arctangent value in double

Return

double	Return the degree value in double

Note

```
value = atan(0)              // 0
value = atan(0.2679492)      // 15
value = atan(0.5773503)      // 30.000002
value = atan(1)              // 45
value = atan(1.732051)       // 60.000004

value = atan(tan(30))        // 30
value = atan(tan(60))        // 60
```

6.22 atan2()

Return the arctangent of the quotient of it arguments

Syntax 1

float **atan2**(
    float,
    float
)

Parameter

float	Input a number in float representing the Y coordinate
float	Input a number in float representing the X coordinate

Return

float	Return the degree value in float

Syntax 2

double **atan2**(
    double,
    double
)

Parameter

double	Input a number in double representing the Y coordinate
double	Input a number in double representing the X coordinate

Return

double	Return the degree value in double

Note

```
value = atan2(2, 1)        // 63.434948
value = atan2(1, 1)        // 45
value = atan2(-1, -1)      // -135
value = atan2(4, -3)       // 126.869896
```

6.23 log()

Return the natural logarithm of the input value

Syntax 1

```
float log(
    float,
    double
)
```

Parameter

float	Input value in float
double	The base of the logarithm

Return

float	Return the logarithm of the input value and the base in float

Syntax 2

```
double log(
    double,
    double
)
```

Parameter

double	Input value in double
double	The base of the logarithm

Return

double	Return the logarithm of the input value and the base in double

Note

```
value = log(16, 2)      // 4
value = log(16, 8)      // 1.3333334
value = log(16, 10)     // 1.20412
value = log(16, 16)     // 1
```

Syntax 3

```
float log(
    float
)
```

Parameter

float	Input value in float

Return

float	Return the natural logarithm of the input value and the base e in float

Syntax 4

```
double log(
    double
)
```

Parameter

double	Input value in double

Return

double	Return the natural logarithm of the input value and the base e in double

Note

```
value = log(16, 2)        // 4
value = log(16)           // 2.7725887
value = log(2)            // 0.6931472
value = log(16)/log(2)    // 2.7725887/0.6931472 = 3.9999998557305
```

6.24 log10()

Return the logarithm of the input value with the base 10

Syntax 1

float **log10**(
    float
)

Parameter

float	Input value in float

Return

float	Return the logarithm of the input value with the base 10 in float

Syntax 2

double **log10**(
    double
)

Parameter

double	Input value in double

Return

double	Return the logarithm of the input value with the base 10 in double

Note

```
value = log(16, 10)     // 1.20412
value = log10(16)       // 1.20412
value = log(500, 10)    // 2.69897
value = log10(500)      // 2.69897
```

6.25 norm2()

Return the second norm of a specified vector.

Syntax 1

float **norm2**(
    float[]
)

Parameter

float[]	A vector whose second norm (or called Euclidean norm, vector magnitude) is to be found.

Return

float	the second norm (or called Euclidean norm, vector magnitude) of a specified vector

Note

$$\|v\| = \sqrt{\sum_{i=1}^{i=N} |v_i|^2}$$

```
float[] vector1 = {3,4}
float[] vector2 = {3,4,5}
float[] vector3 = {3,4,5,6,8}
value = norm2(vector1)        // 5
value = norm2(vector2)        // 7.071068
value = norm2(vector3)        // 12.247449
```

6.26 dist()

Return the distance between the two coordinates.

Syntax 1

float **dist**(
    float[],
    float[]
)

Parameter

float[] The first coordinate $\{X_{1(mm)} \quad Y_{1(mm)} \quad Z_{1(mm)} \quad RX_{1(°)} \quad RY_{1(°)} \quad RZ_{1(°)}\}$

float[] The second coordinate $\{X_{2(mm)} \quad Y_{2(mm)} \quad Z_{2(mm)} \quad RX_{2(°)} \quad RY_{2(°)} \quad RZ_{2(°)}\}$

Return

float The distance between the two coordinates

Note

```
float[] c1 = {100,200,100,30,50,20}
float[] c2 = {100,100,100,50,50,10}
value = dist(c1, c2)          // 100
```

6.27 trans()

Return the displacement and rotation angle from one specified point to another point.

Syntax 1

float[] **trans**(
    float[],
    float[],
    bool
)

Parameter

float[]	First Point	$\{X_{1(mm)} \quad Y_{1(mm)} \quad Z_{1(mm)} \quad RX_{1(°)} \quad RY_{1(°)} \quad RZ_{1(°)}\}$
float[]	Second Point	$\{X_{2(mm)} \quad Y_{2(mm)} \quad Z_{2(mm)} \quad RX_{2(°)} \quad RY_{2(°)} \quad RZ_{2(°)}\}$
bool	The reference coordinate	
	false	Refer to the robot's base(default)
	true	Refer to the first point

Return

float[]	The displacement and rotation angle from first point to second point $\{X_{trans} \quad Y_{trans} \quad Z_{trans} \quad RX_{trans} \quad RY_{trans} \quad RZ_{trans}\}$ Return an empty array if unable to calculate.

Syntax 2

float[] **trans**(
    float[],
    float[]
)

Note

Same as syntax 1. By default, the reference coordinate is set to false for the robot's base.

Original Transformation Matrix = $\begin{bmatrix} R & P \\ 0 & 1 \end{bmatrix}$

$$R_n = \begin{bmatrix} cos(RZ_n)\,cos(RY_n) & -sin(RZ_n)cos(RX_n) + cos(RZ_n)sin(RY_n)sin(RX_n) & sin(RZ_n)sin(RX_n) + cos(RZ_n)sin(RY_n)cos(RX_n) \\ sin(RZ_n)cos(RY_n) & cos(RZ_n)cos(RX_n) + sin(RZ_n)sin(RY_n)sin(RX_n) & -cos(RZ_n)sin(RX_n) + sin(RZ_n)sin(RY_n)cos(RX_n) \\ -sin(RY_n) & cos(RY_n)sin(RX_n) & cos(RY_n)cos(RX_n) \end{bmatrix}$$

First Point = $\begin{bmatrix} R_1 & P_1 \\ 0 & 1 \end{bmatrix}$

Second Point = $\begin{bmatrix} R_2 & P_2 \\ 0 & 1 \end{bmatrix}$

If *reference coordinate* is false (reference coordinate is Robot Base)

$$P_{trans} = P_2 - P_1$$
$$R_{trans} = R_2 * {R_1}^{-1}$$

If *reference coordinate* is true (reference coordinate is First Point)

$$P_{trans} = {R_1}^{-1} * (P_2 - P_1)$$
$$R_{trans} = {R_1}^{-1} * R_2$$

float[] var_P1 = {100, -200, 300, 10, 20, 60}

```
float[] var_P2 = {-400, 200, 50, -20, 30, -45}

float[] var_trans_RB = trans(var_P1, var_P2)
    // {-500,400,-250,-24.615868,-15.565178,-88.613686}
float[] var_trans_i = trans(var_P1, var_P2, true)
    // {176.10095,588.32776,-308.80237,3.7459252,23.13792,-92.46916}
```

6.28 inversetrans()

Return the displacement and rotation angle {x, y, z, rx, ry, rz} opposite to the input displacement and rotation angle {x, y, z, rx, ry, rz}.

Syntax 1

float[] **inversetrans**(
    float[],
    bool
)

Parameter

float[]	The input displacement and rotation angle	$\{X_o \quad Y_o \quad Z_o \quad RX_o \quad RY_o \quad RZ_o\}$
bool	The reference coordinate	
	false	Refer to the robot's base(default)
	true	Refer to the input displacement and the rotation angle

Return

float[]	The displacement and rotation angle $\{X_{inv} \quad Y_{inv} \quad Z_{inv} \quad RX_{inv} \quad RY_{inv} \quad RZ_{inv}\}$ opposite to the input displacement and rotation angle $\{X_o \quad Y_o \quad Z_o \quad RX_o \quad RY_o \quad RZ_o\}$
	Return an empty array if unable to calculate.

Syntax 2

float[] **inversetrans**(
    float[]
)

Note

Same as syntax 1. By default, the reference coordinate is set to false for the robot's base.

Original Transformation Matrix = $\begin{bmatrix} R & P \\ 0 & 1 \end{bmatrix}$

$$R_n = \begin{bmatrix} cos(RZ_n)\,cos(RY_n) & -sin(RZ_n)cos(RX_n) + cos(RZ_n)sin(RY_n)sin(RX_n) & sin(RZ_n)sin(RX_n) + cos(RZ_n)sin(RY_n)cos(RX_n) \\ sin(RZ_n)cos(RY_n) & cos(RZ_n)cos(RX_n) + sin(RZ_n)sin(RY_n)sin(RX_n) & -cos(RZ_n)sin(RX_n) + sin(RZ_n)sin(RY_n)cos(RX_n) \\ -sin(RY_n) & cos(RY_n)sin(RX_n) & cos(RY_n)cos(RX_n) \end{bmatrix}$$

Initial Point = $\begin{bmatrix} R_i & P_i \\ 0 & 1 \end{bmatrix}$

If *reference coordinate* is false (reference coordinate is Robot Base)

$$P_{inv} = -P_i$$
$$R_{inv} = {R_i}^{-1}$$

If *reference coordinate* is true (reference coordinate is the input {x, y, z, rx, ry, rz}, which is equivalent to inverse of Transformation Matrix)

$$P_{inv} = {R_i}^{-1} * (-\ P_i)$$
$$R_{inv} = {R_i}^{-1}$$

```
float[] var_P1 = {100, -200, 300, 10, 20, 60}
float[] var_inv_RB = inversetrans(var_P1)
    // {-100,200,-300,12.483133,-18.590115,-60.283367}
float[] var_inv_i = inversetrans(var_P1, true)
    // {218.38095,142.13216,-268.52972,12.483133,-18.590115,-60.283367}
```

6.29 applytrans()

Return the terminal point computed by applied the displacement and rotation angle to the specified point.

Syntax 1

float[] **applytrans**(
    float[],
    float[],
    bool
)

Parameter

float[]	Initial point $\{X_i \quad Y_i \quad Z_i \quad RX_i \quad RY_i \quad RZ_i\}$
float[]	the displacement and rotation angle $\{X_o \quad Y_o \quad Z_o \quad RX_o \quad RY_o \quad RZ_o\}$
bool	The reference coordinate
false	Refer to the robot's base(default)
true	Refer to the initial point

Return

float[]	the terminal point $\{X_t \quad Y_t \quad Z_t \quad RX_t \quad RY_t \quad RZ_t\}$ computed by applied the displacement and rotation angle to the initial point Return an empty array if unable to calculate.

Syntax 2

float[] **applytrans**(
    float[],
    float[]
)

Note

Same as syntax 1. By default, the reference coordinate is set to false for the robot's base.

Original Transformation Matrix = $\begin{bmatrix} R & P \\ 0 & 1 \end{bmatrix}$

$$R_n = \begin{bmatrix} cos(RZ_n)\,cos(RY_n) & -sin(RZ_n)cos(RX_n) + cos(RZ_n)sin(RY_n)sin(RX_n) & sin(RZ_n)sin(RX_n) + cos(RZ_n)sin(RY_n)cos(RX_n) \\ sin(RZ_n)cos(RY_n) & cos(RZ_n)cos(RX_n) + sin(RZ_n)sin(RY_n)sin(RX_n) & -cos(RZ_n)sin(RX_n) + sin(RZ_n)sin(RY_n)cos(RX_n) \\ -sin(RY_n) & cos(RY_n)sin(RX_n) & cos(RY_n)cos(RX_n) \end{bmatrix}$$

Initial Point = $\begin{bmatrix} R_i & P_i \\ 0 & 1 \end{bmatrix}$

If *reference coordinate* is false (reference coordinate is Robot Base)

$$P_t = P_i + P_{trans}$$
$$R_t = R_{trans} * R_i$$

If *reference coordinate* is true (reference coordinate is Initial point)

$$P_t = P_i + R_i * P_{trans}$$
$$R_t = R_i * R_{trans}$$

```
float[] var_P1 = {100, -200, 300, 10, 20, 60}
float[] var_P2 = {-400, 200, 50, -20, 30, -45}

float[] var_trans_RB = trans(var_P1, var_P2)
    // {-500,400,-250,-24.615868,-15.565178,-88.613686}
```

```
float[] var_trans_i = trans(var_P1, var_P2, true)
    // {176.10095,588.32776,-308.80237,3.7459252,23.13792,-92.46916}

float[] var_apply_RB = applytrans(var_P1, var_trans_RB)
    // {-400,200,50,-20,30,-44.999996}
float[] var_apply_i = applytrans(var_P1, var_trans_i, true)
    // {-400,200,50.000015,-20,30,-45}

float[] var_inv_RB = inversetrans(var_P1)
    // {-100,200,-300,12.483133,-18.590115,-60.283367}
float[] var_inv_i = inversetrans(var_P1, true)
    // {218.38095,142.13216,-268.52972,12.483133,-18.590115,-60.283367}

float[] var_apply_1 = applytrans(var_P1, var_inv_RB)
    // {0,0,0,-4.8045007E-07,1.4295254E-07,4.8365365E-07}
float[] var_apply_2 = applytrans(var_P1, var_inv_i, true)
    // {-3.845248E-06,6.1641267E-06,1.4917891E-06,-1.8922562E-07,-2.1415798E-07,6.352311E-07}
```

6.30 interpoint()

Return the interpolate point between two points according to the specified points and ratio

Syntax 1

float[] **interpoint**(
    float[],
    float[],
    float
)

Parameter

float[]	First Point $\{X_{1(mm)} \quad Y_{1(mm)} \quad Z_{1(mm)} \quad RX_{1(°)} \quad RY_{1(°)} \quad RZ_{1(°)}\}$
float[]	Second Point $\{X_{2(mm)} \quad Y_{2(mm)} \quad Z_{2(mm)} \quad RX_{2(°)} \quad RY_{2(°)} \quad RZ_{2(°)}\}$
float	Ratio

Return

float[]	the linear interpolate point $\{X_i \quad Y_i \quad Z_i \quad RX_i \quad RY_i \quad RZ_i\}$ between initial point and endpoint according to the ratio. Return an empty array if unable to calculate.

Note

$$\{X_i \quad Y_i \quad Z_i \quad RX_i \quad RY_i \quad RZ_i\} = (\{X_2 \quad Y_2 \quad Z_2 \quad RX_2 \quad RY_2 \quad RZ_2\} - \{X_1 \quad Y_1 \quad Z_1 \quad RX_1 \quad RY_1 \quad RZ_1\}) \times Ratio + \{X_1 \quad Y_1 \quad Z_1 \quad RX_1 \quad RY_1 \quad RZ_1\}$$

```
float[] var_P1 = {-388.3831,-199.8061,367.0702,177.4319,1.717448,-46.02005}
float[] var_P2 = {-436.9584,115.7343,371.4378,179.4419,-42.86601,-96.91867}
float[] interp = interpoint(var_P1, var_P2, 0.5)
    // {-412.67075,-42.035904,369.254,172.91898,-20.690556,-69.33843}
```

6.31 changeref()

Return the new coordinate value described with the new base converted from the original coordinate value through the base conversion. In the process of the conversion, the physical position of the original point in the world of the coordinates will remain the same, the change takes effects on its descriptions of the reference coordinates and the corresponding coordinate values.

Syntax 1

float[] **changeref**(
    float[],
    float[],
    float[]
)

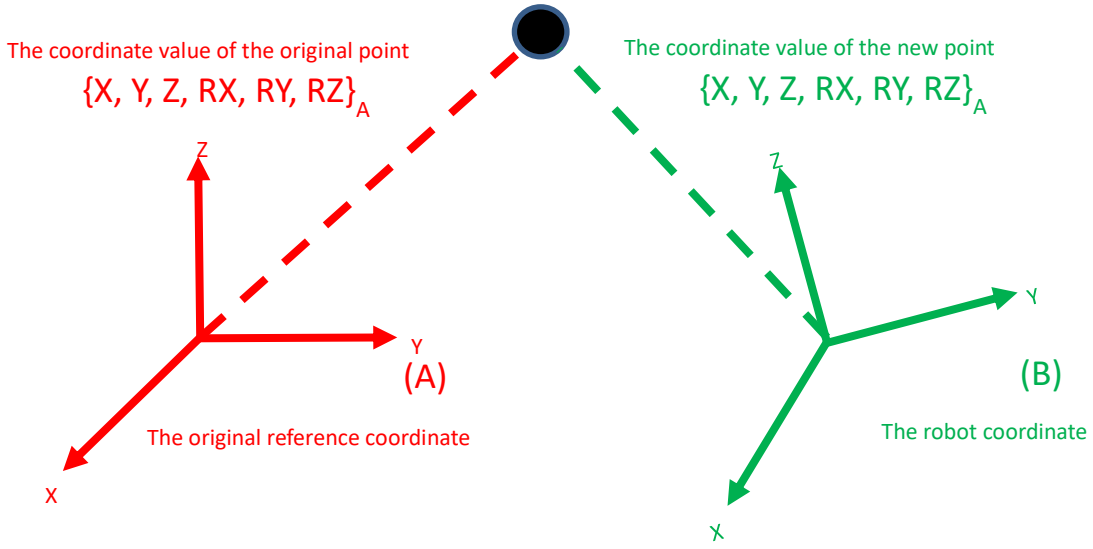
Parameter

float[]	The coordinate value of the original point $\{X_o \quad Y_o \quad Z_o \quad RX_o \quad RY_o \quad RZ_o\}_A$
float[]	The original reference base $\{X_{oa} \quad Y_{oa} \quad Z_{oa} \quad RX_{oa} \quad RY_{oa} \quad RZ_{oa}\}_A$
float[]	The new reference base $\{X_n \quad Y_n \quad Z_n \quad RX_n \quad RY_n \quad RZ_n\}_B$

Return

float[]	The coordinate value of the new point $\{X_{nb} \quad Y_{nb} \quad Z_{nb} \quad RX_{nb} \quad RY_{nb} \quad RZ_{nb}\}_B$ Return an empty array if unable to calculate.

Note



P1 = {-431.927, -140.6103, 368.7306, -179. 288, -0.6893783, -105.8449}
RobotBase = {0, 0, 0, 0, 0, 0}
base1 = {-431.93, -140.61, 368.73, -57.70, -44.98, 33.62}
float[] f0 = **changeref**(Point["P1"].Value, Base["RobotBase"].Value, Base["base1"].Value)
// f0 = {0.0020519744,1.9731047E-05,-0.0022721738,113.94231,14.9346,-123.19886}
// Convert the value of "P1" in the base "RobotBase" to the value of a point in the base "base1"

Syntax 2

float[] **changeref**(
    float[],

float[]
)

Parameter

float[] The coordinate value of the original point $\{X_o \quad Y_o \quad Z_o \quad RX_o \quad RY_o \quad RZ_o\}_A$

float[] The original reference base $\{X_{oa} \quad Y_{oa} \quad Z_{oa} \quad RX_{oa} \quad RY_{oa} \quad RZ_{oa}\}_A$

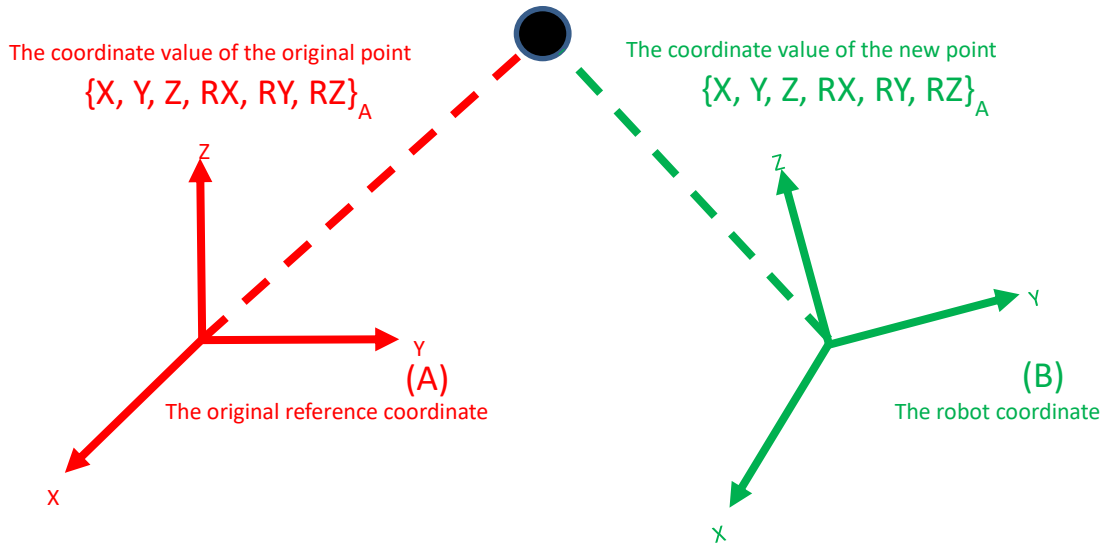
Return

float[] The coordinate value of the new point $\{X_{nr} \quad Y_{nr} \quad Z_{nr} \quad RX_{nr} \quad RY_{nr} \quad RZ_{nr}\}_R$

Return an empty array if unable to calculate.

Note

The usage is the same as Syntax1's except assuming the robot base $\{0 \quad 0 \quad 0 \quad 0 \quad 0 \quad 0\}_R$ as the default new reference base.




```
base1 = {-431.93, -140.61, 368.73, -57.70, -44.98, 33.62}
f0 = {0.002052, 0.000020, -0.002272, 113.9423, 14.9346, -123.1989}
float[] f1 = changeref(f0, Base["base1"].Value)
// f1 = {-431.927,-140.6103,368.7306,-179.288,-0.6893424,-105.84492}
```

6.32 points2coord()

Based on the input points, calculate the coordinate plane of the input points and return the values of the plane parameters converted by the three points on the plane.

Syntax 1

float[] **points2coord**(
    float[],
    float[],
    float[]
)

Parameters

float[] The origin coordinates in the coordinate plane
$X_{1(mm)}$ $Y_{1(mm)}$ $Z_{1(mm)}$ $RX_{1(°)}$ $RY_{1(°)}$ $RZ_{1(°)}$

float[] Any point on the X axis in the plane $X_{2(mm)}$ $Y_{2(mm)}$ $Z_{2(mm)}$ $RX_{2(°)}$ $RY_{2(°)}$ $RZ_{2(°)}$

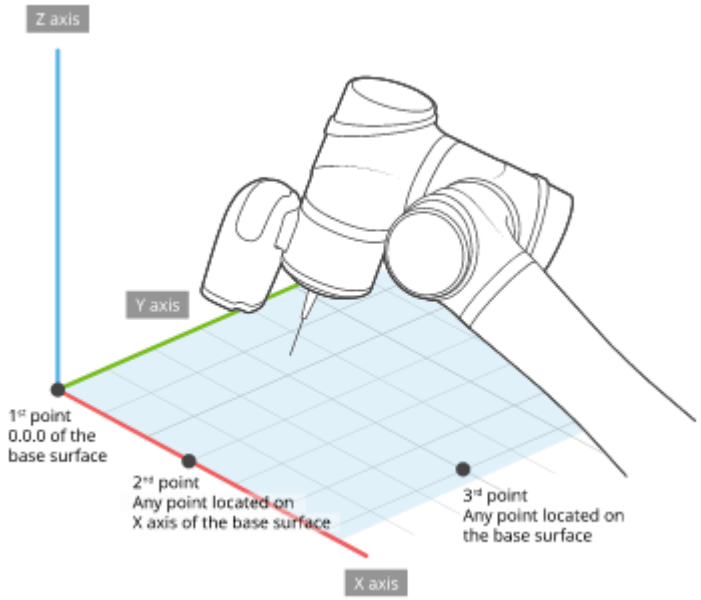
float[] Any point on the +X and +Y in the plane
$X_{3(mm)}$ $Y_{3(mm)}$ $Z_{3(mm)}$ $RX_{3(°)}$ $RY_{3(°)}$ $RZ_{3(°)}$

* The input points above are required to be described in the same base.

Return

float[] The value of the plane parameter formed by the three points on the plane
$X_{p(mm)}$ $Y_{p(mm)}$ $Z_{p(mm)}$ $RX_{p(°)}$ $RY_{p(°)}$ $RZ_{p(°)}$
that coincided with the origin of the plane
$X_{1(mm)}$ $Y_{1(mm)}$ $Z_{1(mm)}$
and calculated with the corners of
$X_{2(mm)}$ $Y_{2(mm)}$ $Z_{2(mm)}$ $RX_{2(°)}$ $RY_{2(°)}$ $RZ_{2(°)}$
and
$X_{3(mm)}$ $Y_{3(mm)}$ $Z_{3(mm)}$ $RX_{3(°)}$ $RY_{3(°)}$ $RZ_{3(°)}$

Note



Supposed there are three points: P1, P2, and P3
Point["P1"].Value = {389.9641,-4.797323,416.2175,177.3384,0.9190881,91.07789}
Point["P2"].Value = {365.0222,137.3036,423.2249,177.4598,0.9549707,112.4033}
Point["P3"].Value = {546.7307,94.02614,385.1812,176.3468,0.5975906,95.82078}

```
Base["points2coord_b1"].Value = points2coord(Point["P1"].Value, Point["P2"].Value,
Point["P3"].Value)
  // {389.9641,-4.797323,416.2175,-168.6551,-2.780696,99.9553}
Point["P4"].Value = {0,0,0,0,0,0}
ChangeBase("points2coord_b1")
PTP("CPP",Point["P4"].Value,10,200,0,false)
```

Syntax 2

```
float[] points2coord(
    float, float, float,
    float, float, float,
    float, float, float
)
```

Parameter

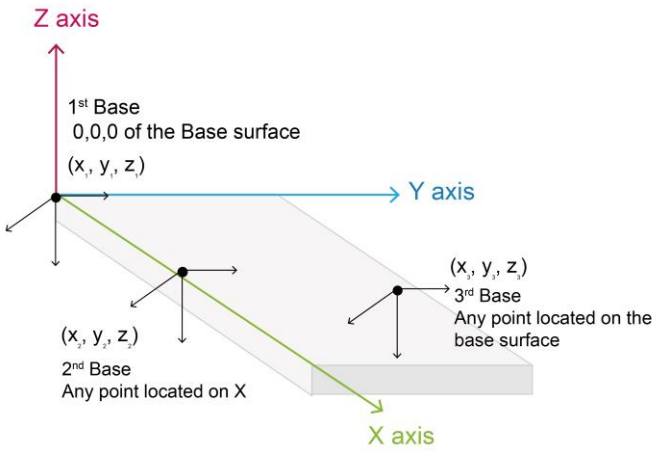
float, float, float	The origin coordinates in the coordinate plane to calculate $X_{1(mm)}$ $Y_{1(mm)}$ $Z_{1(mm)}$
float, float, float	The coordinates of any point on the X axis in the coordinate plane to calculate $X_{2(mm)}$ $Y_{2(mm)}$ $Z_{2(mm)}$
float, float, float	The coordinates of any point in the coordinate plane to calculate $X_{3(mm)}$ $Y_{3(mm)}$ $Z_{3(mm)}$

* The input points above are required to be described in the same base.

Return

float[]	Definition parameters of the coordinate plane to calculate. $X_{p(mm)}$ $Y_{p(mm)}$ $Z_{p(mm)}$ $RX_{p(°)}$ $RY_{p(°)}$ $RZ_{p(°)}$

Note




```
Base["points2coord_2"].Value = points2coord(260,0,360,260,100,360,100,0,360)
  // {260,0,360,0,0,90}
Point["P1"].Value = {0,0,0,180,0,0}
ChangeBase("points2coord_2")
PTP("CPP",Point["P1"].Value,10,200,0,false)
```

6.33 intercoord()

Convert two input planes into a new plane.

Syntax 1

float[] **intercoord**(
    float[],
    float[]
)

Parameters

float[] The first input plane $X_{1(mm)}$ $Y_{1(mm)}$ $Z_{1(mm)}$ $RX_{1(°)}$ $RY_{1(°)}$ $RZ_{1(°)}$

float[] The second input plane $X_{2(mm)}$ $Y_{2(mm)}$ $Z_{2(mm)}$ $RX_{2(°)}$ $RY_{2(°)}$ $RZ_{2(°)}$

* The input points above are required to be described in the same base.

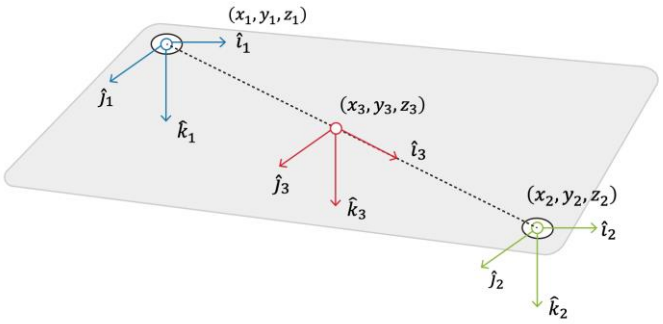
Return

float[] The new plane converted by the two input planes.

$X_{3(mm)}$ $Y_{3(mm)}$ $Z_{3(mm)}$ $RX_{3(°)}$ $RY_{3(°)}$ $RZ_{3(°)}$

Note

$x_3 = (x_1 + x_2)/2$
$y_3 = (y_1 + y_2)/2$
$z_3 = (z_1 + z_2)/2$
$\hat{\imath}_3 = (x_2 - x_1, y_2 - y_1, z_2 - z_1)$
$\hat{\jmath}_3 = \hat{k}_1 \times \hat{\imath}_3$
$\hat{k}_3 = \hat{\imath}_3 \times \hat{\jmath}_3$



Supposed there are vision landmark jobs: vb_1 and vb_2
vb_1 outputs Base["vision_vb_1"].Value = {-69.73,380.02,141.79,-176.11,1.13,-121.27}
vb_2 outputs Base["vision_vb_2"].Value = {58.81,613.03,140.7,171.62,-0.89,0.8}

Base["mix_base"].Value = **intercoord**(Base["vision_vb_1"].Value, Base["vision_vb_2"].Value)
// {-5.460001,496.52502,141.245,176.06546,0.23468152,61.116673}

6.34 coorshift()

Calculate a new coordinate by adding a shift value to the original coordinate, where the shift depends on the position and direction of the original coordinate.

Syntax 1

float[] **coordshift**(
    float[],
    float[]
)

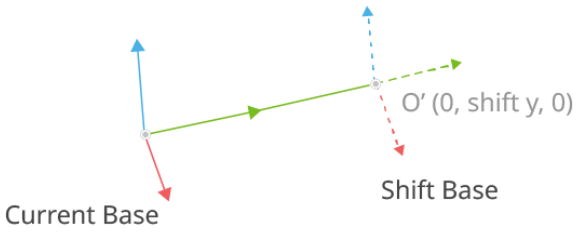
Parameters

float[]	base value	$X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$
float[]	shift value	$X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Return

float[]	the new coordinate value calculated by the given position and direction of the coordinate and the shift value. $X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Note




```
Base["base1"].Value = {200,100,300,0,15,0}
Base["base2"].Value = {0,0,0,0,0,-90}
float[] var_shift = {10,50,0,0,0,0}

Base["base2"].Value = coordshift(Base["base2"].Value, var_shift)
    // {50, -10, 0, 0, 0, -90}
float[] var_baseNew = coordshift(Base["base1"].Value, Base["base2"].Value)
    // {248.2963, 90, 287.05905, -15, 0, -90}
```

6.35 inversekin()

Convert the Cartesian coordinates to joint angles.

Syntax 1

float[] **inversekin**(
    float[]
)

Parameters

float[]	The coordinates to be converted: $\{X_{(mm)} \quad Y_{(mm)} \quad Z_{(mm)} \quad RX_{(°)} \quad RY_{(°)} \quad RZ_{(°)}\}$

Return

float[]	By the current pose configuration, return the joint angle elements: $\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$ If calculation fails, return an empty array.

Note

```
float[] p1 = {663.9, -181.8, 666.35, 180, 0, 90}      // The Cartesian coordinates
float[] joint1 = inversekin(p1)     // Convert the Cartesian coordinates to joint angles.
                                    // Take TM12S as an example: joint1 = {0,0,90,0,90,0}
float[] joint2 = inversekin(Point["P2"].Value)
// Available point parameterization for conversion.
float[] joint3 = inversekin({9999, 9999, 9999, 0, 0, 0})
// Out of scope, return an empty array {}.
```

Syntax 2

float[] **inversekin**(
    float[],
    int[]
)

Parameters

float[]	The coordinates to be converted: $\{X_{(mm)} \quad Y_{(mm)} \quad Z_{(mm)} \quad RX_{(°)} \quad RY_{(°)} \quad RZ_{(°)}\}$
int[]	Pose configuration parameters: $\{Config_1 \quad Config_2 \quad Config_3\}$

Return

float[]	By the pose configuration parameters, return the joint angle elements: $\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$ If calculation fails, return an empty array.

Note

```
float[] p1 = {663.9, -181.8, 666.35, 180, 0, 90}      // The Cartesian coordinates
float[] joint1 = inversekin(p1, {1,2,4})
// Convert the Cartesian coordinate values to joint angles with the pose configuration parameters.
// Take TM12S as an example: joint1 = {149.37149,0,-90,0,-90,-30.628504}
```

Syntax 3

float[] **inversekin**(
    float[],
    float[]
)

Parameters

float[]	The coordinates to be converted:

$\{X_{(mm)} \quad Y_{(mm)} \quad Z_{(mm)} \quad RX_{(°)} \quad RY_{(°)} \quad RZ_{(°)}\}$

float[] The reference joint base, for the six elements of the robot joint:
$\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$

Return

float[] By the reference joint base, return the joint angle elements::
$\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$
If calculation fails, return an empty array.

Note

```
float[] p1 = {663.9, -181.8, 666.35, 180, 0, 90}      // The Cartesian coordinates
float[] joint_ref = {0,-30,120,0,90,0}          // The reference joint base
float[] joint1 = inversekin(p1, joint_ref)
// Convert the Cartesian coordinate values to the reference joint base with the joint angles.
// Take TM12S as an example: joint1 = {0,0,90,0,90,0}
```

6.36 forwardkin()

Convert joint angles to the Cartesian coordinates.

Syntax 1

float[] **forwardkin**(
    float[]
)

Parameters

float[]	Joint angle elements to be converted: $\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$

Return

float[]	Return coordinate elements: $\{X_{(mm)} \quad Y_{(mm)} \quad Z_{(mm)} \quad RX_{(°)} \quad RY_{(°)} \quad RZ_{(°)}\}$ If calculation fails, return an empty array.

Note

```
float[] joint1 = {0,0,90,0,90,0}    // Joint angles
float[] p1 = forwardkin(joint1)     // Convert joint angles to the Cartesian coordinates.
                                    // Take TM12S as an example: p1 = {663.9,-181.8,666.35,180,0,90}
float[] p2 = forwardkin(Point["P2"].Joint)  // Available point parameterization for conversion.
```

6.37 joint2pose()

Convert joint angles to the pose configuration parameters.

Syntax 1

int[] **joint2pose**(
    float[]
)

Parameters

float[]	Joint angle elements to be converted: $\{J_{1(°)} \quad J_{2(°)} \quad J_{3(°)} \quad J_{4(°)} \quad J_{5(°)} \quad J_{6(°)}\}$

Return

int[]	Return the pose configuration parameters: $\{Config_1 \quad Config_2 \quad Config_3\}$ If the calculation fails, return an empty array.

Note

```
float[] joint1 = {0,0,90,0,90,0}        // Joint angles
int[] config = joint2pose(joint1)       // Convert the joint angles to the pose configuration
                                        parameters. config = {0,2,4}
```

7. File Functions

- The file functions are capable of operations related to file reading, writing, or inquiry.
- File path
  1. Local path. Available in the directories named **TextFiles**, **XmlFiles**, and **TMcraft** only.

     FileName.txt — The directory default to .\TextFiles (File path the same as .\TextFiles\FileName.txt)

     .\TextFiles\FileName.txt — The file is in the local directory named **TextFiles**.

     .\XmlFiles\FileName.xml — The file is in the local directory named **XmlFiles**.

     .\XmlFiles\folder\file — The subdirector is in the local directory named **XmlFiles**.

     ..\folder — Unavailable.

     .\TextFiles\..\..\folder — Unavailable.

     Void for absolute paths.

     C:\file1 — Void.

     D:\folder\file2 — Void.

     \TextFiles\FileName.txt — Void.
  2. External device path. Available to USB drives or SSD labelled **TMROBOT**.

     \USB\TMROBOT — The root directory of the external USB drive.
  3. Remote path. Available with the Network service in TMflow.

     \\127.0.0.1\shared — SMB / CIFS

     ftp://127.0.0.1 — FTP
- The path is not case sensitive. For example, the paths below all point to the same file.

  .\TextFiles\FileName.txt
  .\textfiles\fileName.txt
  .\Textfiles\Filename.TXT
- The path is available for pointing to subdirectories such as:

  subfolder\file
  .\TextFiles\subfolder1\subfolder2\file
  .\XmlFiles\subfolder\file
  \USB\TMROBOT\subfolder\file
  \\127.0.0.1\shared\subfolder\file
- The maximum file size is limited to 10MB (10485760 Bytes).
- The type of the array to read or write depends on the definition of the array.

7.1 File_ReadBytes()

Read the file content and return in the type of byte[].

Syntax 1

byte[] **File_ReadBytes**(
    string
)

Parameter

string	File path

Return

byte[]	Return the file content in the type of byte[].

Note

```
.\TextFiles\SampleFile1.txt
1|  1Hello World!
2|  1Hello TM Robot!
```

```
byte[] var_bb1 = File_ReadBytes("sampleFile1.txt")
// {0x31,0x48,0x65,0x6C,0x6C,0x6F,0x20,0x57,0x6F,0x72,0x6C,0x64,0x21,0x0D,0x0A,
   0x31,0x48,0x65,0x6C,0x6C,0x6F,0x20,0x54,0x4D,0x20,0x52,0x6F,0x62,0x6F,0x74,0x21}
byte[] var_bb2 = File_ReadBytes(".\TextFiles\SampleFile1.txt")
// {0x31,0x48,0x65,0x6C,0x6C,0x6F,0x20,0x57,0x6F,0x72,0x6C,0x64,0x21,0x0D,0x0A,
   0x31,0x48,0x65,0x6C,0x6C,0x6F,0x20,0x54,0x4D,0x20,0x52,0x6F,0x62,0x6F,0x74,0x21}
byte[] var_bb3 = File_ReadBytes("C:\SampleFile1.txt")     // Error. Void for absolute paths.
byte[] var_bb4 = File_ReadBytes(".\SampleFile1.txt")
// Error. The file is in the local directory named TextFiles or XmlFiles.
byte[] var_bb5 = File_ReadBytes("SampleFileXX.txt")// Error. The file does not exist.
```

7.2 File_ReadText()

Read the file content and return in the type of string.

Syntax 1

string **File_ReadText**(
    string
)

Parameter

string		File path

Return

string		Return the file content in the type of string.

Note

```
.\TextFiles\SampleFile1.txt
1|  1Hello World!
2|  1Hello TM Robot!
```

```
string var_s1 = File_ReadText("sampleFile1.txt")
// "1Hello World!\u0D0A1Hello TM Robot!"
string var_s2 = File_ReadText(".\TextFiles\SampleFile1.txt")
// "1Hello World!\u0D0A1Hello TM Robot!"
```

* \u0D0A denotes a new line character but not a string value.

```
string var_s3 = File_ReadText("C:\SampleFile1.txt")
// Error. Void for absolute paths.
string var_s4 = File_ReadText(".\SampleFile1.txt")
// Error. The file is in the local directory named TextFiles or XmlFiles.
```

7.3 File_ReadLines()

Read the file content and return in the type of string separated by new line characters .

Syntax 1

string[] **File_ReadLines**(
    string
)

Parameter

string	File path

Return

string[]	Return the file content in the type of string separated by new line characters.

Syntax 2

string[] **File_ReadLines**(
    string,
    int,
    int
)

Parameter

string	File path
int	The number of the line to start to read
int	The amount of the lines to read

Return

string[]	Return the file content in the type of string separated by new line characters. If the number of the line to start to read <= 0, it returns an empty array. If the number of the line to start to read > the total number of lines, it returns an empty array. If the amount of the lines to read <= 0，it returns from the first line to the last line. If the amount of the lines to read > the total number of lines，it returns from the first line to star to read to the last line.

Syntax 3

string[] **File_ReadLines**(
    string,
    int
)

Note

Same as Syntax 2 with the parameter of amount of the lines to read defaults to 0 and returns to the last line. **File_ReadLines**(string,int,int) => **File_ReadLines**(string,int,0)

Note

```
.\TextFiles\SampleFile2.txt
1|  2Hello World!
2|  2Hello TM Robot!
3|  2Hi TM Robot!
```

```
string[] var_ss = {""}
```

```
var_ss = File_ReadLines("SampleFile2.txt")      // {"2Hello World!", "2Hello TM Robot!", "2Hi TM Robot!"}
var_ss = File_ReadLines("SampleFile2.txt", 1, 2)// {"2Hello World!", "2Hello TM Robot!"}
var_ss = File_ReadLines("SampleFile2.txt", 2, 2)// {"2Hello TM Robot!", "2Hi TM Robot!"}
var_ss = File_ReadLines("SampleFile2.txt", 3, 2)// {"2Hi TM Robot!"}   // Tops the total number of lines. Returns to the last line.
var_ss = File_ReadLines("SampleFile2.txt", 0)       // {}          // empty array
var_ss = File_ReadLines("SampleFile2.txt", 4)       // {}          // empty array
int var_len = Length(var_ss)                        // 0
var_ss = File_ReadLines("SampleFile2.txt", 3, 0)    // {"2Hi TM Robot!"}   // Returns from line 3 to the last line.
```

```
.\TextFiles\SampleFile3.txt
1|
```

```
var_ss = File_ReadLines("SampleFile3.txt") // {""} // var_ss[0] = ""
var_len = Length(var_ss)                   // 1
```

7.4 File_NextLine()

Record the last read file path, and continue to read the next line of the file content or open the file to read.

Syntax1

string **File_NextLine**(
    string
)

Parameter

string	File path

Return

string	If the same as the last read file path, it returns the next line of the file content. If different from the last read file path, it opens the file and returns the first line of the file content. If read the end of the file, it returns an empty string.

Syntax 2

string **File_NextLine**(
    string,
    bool
)

Parameter

string	File path
bool	Whether open the file to read or not
false	Try the file path. Continue to read the next line if the same. Open the file to read if different.
true	Open the file and read the first line.

Return

string	Whether open the file to read or not false If the same as the last read file path, it returns the next line of the file content. If different from the last read file path, it opens the file and returns the first line of the file content. Whether open the file to read or not true It opens the file and returns the first line of the file content. If read the end of the file, it returns an empty string.

Syntax 3

string **File_NextLine**(
)

Parameter

void	No parameter

Return

string	Return the next line of the file content in the last record to read or returns an empty string if not read.

Note

```
.\TextFiles\SampleFile4.txt
1|  4Hello World!
```

```
.\TextFiles\SampleFile5.txt
1|  5Hello World!
```

```
2|
3|  4Hello TM Robot!
```

```
2|  5Hello TM Robot!
3|  5Hi TM Robot!
```

```
string var_s = ""
var_s = File_NextLine()                                  // ""              // Not open the file to read.
var_s = File_NextLine("SampleFile4.txt")                 // "4Hello World!"
var_s = File_NextLine("SampleFile4.txt")                 // ""              // Continue to read the next line.
var_s = File_NextLine("SampleFile5.txt")                 // "5Hello World!"
                                                         // Different file path. Open the file to read.
var_s = File_NextLine("SampleFile4.txt")                 // "4Hello World!"
                                                         // Different file path. Open the file to read.
var_s = File_NextLine("SampleFile4.txt")                 // ""              // Continue to read the next line
var_s = File_NextLine("SampleFile4.txt")                 // "4Hello TM Robot!"
var_s = File_NextLine("SampleFile4.txt")                 // ""          // Continue to read the next line (to the
                                                         EOF)
var_s = File_NextLine("SampleFile4.txt", true)           // "4Hello World!"
                                                         // Open the file to read the first line.
var_s = File_NextLine("SampleFile4.txt", true)           // "4Hello World!"
                                                         // Open the file to read the first line.
var_s = File_NextLine("SampleFile4.txt", false)          // ""
                                                         // Continue to read the next line
var_s = File_NextLine()                                  // "4Hello TM Robot!"
```

* To determine a blank line or the end of the file, use syntax 4 with the size of string[].
* Or, use File_NextEOF() to determine the end of the file.

Syntax 4

string[] **File_NextLine**(
    string,
    int
)

Parameter

string		File path
int		Parameters to read
	0	Try the file path. Continue to read the next line if the same. Open the file to read if different.
	1	Open the file and read the first line.
	2	Open the file without reading. Returns a empty array.

Return

string[]	Return strings in the next line of the file content in an array. If the array size is 1, it denotes read the strings in the next line. If the array size is 0, it denotes read the end of the file already.

Syntax 5

string[] **File_NextLine**(
    int
)

Parameter

int	Parameters to read

0	Try the file path. Continue to read the next line if the same. Open the file to read if different.
1	Open the file and read the first line.
2	Open the file without reading. Returns a empty array.

Return

string[]	Return strings in the next line of the file content in an array in the last record to read or an empty string array if not read. If the array size is 1, it denotes read the strings in the next line. If the array size is 0, it denotes read the end of the file already.

Note

```
.\TextFiles\SampleFile4.txt
1|  4Hello World!
2|
3|  4Hello TM Robot!
```

```
.\TextFiles\SampleFile5.txt
1|  5Hello World!
2|  5Hello TM Robot!
3|  5Hi TM Robot!
```

```
string[] var_ss = {""}
var_ss = File_NextLine(0)                          // {}          // Not open the file to read.
var_ss = File_NextLine("SampleFile4.txt", 0)// {"4Hello World!"}
var_ss = File_NextLine("SampleFile4.txt", 0)// {""} // Continue to read the next line.
var_ss = File_NextLine("SampleFile5.txt", 0)// {"5Hello World!"}
                                                   // Different file path. Open the file to read.
var_ss = File_NextLine("SampleFile4.txt", 0)// {"4Hello World!"}
                                                   // Different file path. Open the file to read.
var_ss = File_NextLine("SampleFile4.txt", 0)// {""} // Continue to read the next line.
int var_len = Length(var_ss)                             // 1
var_ss = File_NextLine("SampleFile4.txt", 0)// {"4Hello TM Robot!"}
var_ss = File_NextLine("SampleFile4.txt", 0)// {}
                                                   // Continue to read the next line (to the EOF)
var_len = Length(var_ss)                           // 0
var_ss = File_NextLine("SampleFile4.txt", 1)// {"4Hello World!"}
                                                   //Open the file and read the first line.
var_ss= File_NextLine("SampleFile4.txt", 2) // {}
                                                   //Open the file without reading.
var_len = Length(var_ss)                           // 0
var_ss = File_NextLine("SampleFile4.txt")    // {"4Hello World!"}
                                                   // Continue to read the next line.
var_ss = File_NextLine(0)                          // {""}
                                                   // Continue to read the next line.
var_ss = File_NextLine(0)                          // {"4Hello TM Robot!"}
var_ss = File_NextLine(0)                          // {}
```

7.5 File_NextEOF()

Try the last read file path for reading to the end of the file already.

Syntax 1

bool **File_NextEOF**(
)

Parameter

void No parameter but needs to use with File_NextLine()

Return

bool Return true if not read.

false Not read to the end of the file.

true Not open the file or read to the end of the file.

Note

```
.\TextFiles\SampleFile4.txt
1|  4Hello World!
2|
3|  4Hello TM Robot!
```

```
bool var_eof = File_NextEOF()              // true       // Not open the file to read.
string var_s = ""
var_s = File_NextLine("SampleFile4.txt")   // "4Hello World!"
var_eof = File_NextEOF()                   // false
var_s = File_NextLine("SampleFile4.txt")   // ""
var_eof = File_NextEOF()                   // false
var_s = File_NextLine("SampleFile4.txt")   // 4Hello TM Robot!"
var_eof = File_NextEOF()                   // true
var_s = File_NextLine("SampleFile4.txt")   // ""

File_NextLine("SampleFile4.txt", 2)        // Open the file without reading.
var_eof = File_NextEOF()                   // false
```

7.6 File_WriteBytes()

Put the data content into an array in byte and write to a file.

Syntax 1

bool **File_WriteBytes**(
string,
?,
int,
int,
int
)

Parameter

string	File path	
?	Values to write. Eligible for integers, floating-point numbers, Booleans, strings, or arrays. Values will be converted with Little Endian, and strings will be converted with UTF8.	
int	Overwrite the file or append to the file.	
	0	Over the file. If not existed, create a new file.
	1	Append to the file. If not existed, create a new file.
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 2

bool **File_WriteBytes**(
string,
?,
int,
int
)

Note

Same as Syntax 1. Set the length of the value to write to 0 writing up to the data ends.
File_WriteBytes(string,?,int,int) => **File_WriteBytes**(string,?,int,int,0)

Syntax 3

bool **File_WriteBytes**(
string,
?,
int
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 writing up to the data ends.

File_WriteBytes(string,?,int) => **File_WriteBytes**(string,?,int,0,0)

Syntax 4

bool **File_WriteBytes**(
string,
?
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 overwriting the file up to the data ends.

File_WriteBytes(string,?) => **File_WriteBytes**(string,?,0,0,0)

```
byte[] var_bb1 = {0x00, 0x01, 0x02, 0x03, 0x04, 0x05, 0x06, 0x07, 0x08}
byte[] var_bb2 = {0x30, 0x31, 0x32, 0x33, 0x34, 0x35, 0x36, 0x37, 0x38}
byte[] var_bb3 = {}
bool flag = false
var_flag = File_WriteBytes("writebytes.txt", var_bb1) // Overwrite var_bb1 to the file
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  00 01 02 03 04 05 06 07 08
```

```
var_flag = File_WriteBytes("writebytes.txt", var_bb2) // Overwrite var_bb2 to the file
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  30 31 32 33 34 35 36 37 38
```

```
var_flag = File_WriteBytes("writebytes.txt", var_bb3) // Overwrite var_bb3 to the file
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000
```

```
File_WriteBytes("writebytes.txt", var_bb1, 1)// Append var_bb1 to the file
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  00 01 02 03 04 05 06 07 08
```

```
File_WriteBytes("writebytes.txt", var_bb2, 1)// Append var_bb2 to the file
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  00 01 02 03 04 05 06 07 08 30 31 32 33 34 35 36
00000010  37 38
```

```
File_WriteBytes("writebytes.txt", var_bb1, 1, 3)
// Append var_bb1 to the file starting from index 3 to the end.
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  00 01 02 03 04 05 06 07 08 30 31 32 33 34 35 36
00000010  37 38 03 04 05 06 07 08
```

```
File_WriteBytes("writebytes.txt", var_bb2, 1, 3, 2)
// Append var_bb2 to the file starting from index 3 for the length of 2
```

```
writebytes.txt
Offset(h) 00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F
00000000  00 01 02 03 04 05 06 07 08 30 31 32 33 34 35 36
00000010  37 38 03 04 05 06 07 08 33 34
```

```
File_WriteBytes("writebytes.txt", var_bb1, 1, -1)
// -1 illegitimate value // Append var_bb1 to the file starting from index 0 to the end.
```

writebytes.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	00	01	02	03	04	05	06	07	08	30	31	32	33	34	35	36
00000010	37	38	03	04	05	06	07	08	33	34	00	01	02	03	04	05
00000020	06	07	08													

File_WriteBytes("writebytes.txt", var_bb2, 1, 0, 100)
// Append var_bb2 to the file starting from index 0 for the length of 100 or to the end.

writebytes.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	00	01	02	03	04	05	06	07	08	30	31	32	33	34	35	36
00000010	37	38	03	04	05	06	07	08	33	34	00	01	02	03	04	05
00000020	06	07	08	30	31	32	33	34	35	36	37	38				

? byte var_n1 = 100 // Convert the value with Little Endian.
File_WriteBytes("writebytes2.txt", var_n1, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64															

? byte[] var_n2 = {100, 200} // Convert every value in the array with Little Endian one after another.
File_WriteBytes("writebytes2.txt", var_n2, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64	64	C8													

? int var_n3 = 10000
File_WriteBytes("writebytes2.txt", var_n3, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64	64	C8	10	27	00	00									

? int[] var_n4 = {10000, 20000, 80000}
File_WriteBytes("writebytes2.txt", var_n4, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64	64	C8	10	27	00	00	10	27	00	00	20	4E	00	00	80
00000010	38	01	00													

? float var_n5 = 1.234
File_WriteBytes("writebytes2.txt", var_ n5, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64	64	C8	10	27	00	00	10	27	00	00	20	4E	00	00	80
00000010	38	01	00	B6	F3	9D	3F									

? float[] var_n6 = {1.23, 4.56, -7.89}
File_WriteBytes("writebytes2.txt", var_n6, 1)

writebytes2.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	64	64	C8	10	27	00	00	10	27	00	00	20	4E	00	00	80
00000010	38	01	00	B6	F3	9D	3F	A4	70	9D	3F	85	EB	91	40	E1
00000020	7A	FC	C0													

? double var_n7 = -1.2345
File_WriteBytes("writebytes3.txt", var_ n7, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF								

? double[] var_n8 = {1.23, -7.89}
File_WriteBytes("writebytes3.txt", var_n8, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF	AE	47	E1	7A	14	AE	F3	3F
00000010	8F	C2	F5	28	5C	8F	1F	C0								

? bool var_n9 = true // Convert true to 1 and false to 0.
File_WriteBytes("writebytes3.txt", var_n9, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF	AE	47	E1	7A	14	AE	F3	3F
00000010	8F	C2	F5	28	5C	8F	1F	C0	01							

? bool[] var_n10 = {true, false, true, false, false, true, true}
File_WriteBytes("writebytes3.txt", var_n10, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF	AE	47	E1	7A	14	AE	F3	3F
00000010	8F	C2	F5	28	5C	8F	1F	C0	01	01	00	01	00	00	01	01

? string var_n11 = "ABCDEFG" // Convert the string into UTF8.
File_WriteBytes("writebytes3.txt", var_n11, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF	AE	47	E1	7A	14	AE	F3	3F
00000010	8F	C2	F5	28	5C	8F	1F	C0	01	01	00	01	00	00	01	01
00000020	41	42	43	44	45	46	47									

? string[] var_n12 = {"ABC", "DEF", "達明機器人" }
File_WriteBytes("writebytes3.txt", var_n12, 1)

writebytes3.txt

Offset(h)	00	01	02	03	04	05	06	07	08	09	0A	0B	0C	0D	0E	0F
00000000	8D	97	6E	12	83	C0	F3	BF	AE	47	E1	7A	14	AE	F3	3F
00000010	8F	C2	F5	28	5C	8F	1F	C0	01	01	00	01	00	00	01	01
00000020	41	42	43	44	45	46	47	41	42	43	44	45	46	E9	81	94
00000030	E6	98	8E	E6	A9	9F	E5	99	A8	E4	BA	BA				

7.7 File_WriteText()

Put the data content in a string and write to a file.

Syntax 1

bool **File_WriteText**(
string,
?,
int,
int,
int
)

Parameter

string	File path	
?	Values to write. Eligible for integers, floating-point numbers, Booleans, strings, or arrays.	
int	Overwrite the file or append to the file.	
	0	Over the file. If not existed, create a new file.
	1	Append to the file. If not existed, create a new file.
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length -1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 2

bool **File_WriteText**(
string,
?,
int,
int
)

Note

Same as Syntax 1. Set the length of the value to write to 0 writing up to the data ends.
File_WriteText(string,?,int,int) => **File_WriteText**(string,?,int,int,0)

Syntax 3

bool **File_WriteText**(
string,
?,
int
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 writing

up to the data ends.

File_WriteText(string,?,int) => **File_WriteText**(string,?,int,0,0)

Syntax 4

File_WriteText(string,?) => **File_WriteText**(string,?,0,0,0)

```
string var_s1 = "Hi TM Robot"
string var_s2 = "達明機器人"
bool var_flag = false
var_flag = File_WriteText("writetext.txt", var_s1)  // Overwrite "Hi TM Robot" to the file
```

writetext.txt

```
1|  Hi TM Robot
```

```
var_flag = File_WriteText("writetext.txt", var_s2)  // Overwrite "達明機器人" to the file
```

writetext.txt

```
1|  達明機器人
```

```
var_flag = File_WriteText("writetext.txt", var_s1, 1)     // Append "Hi TM Robot" to the file
```

writetext.txt

```
1|  達明機器人Hi TM Robot
```

```
var_flag = File_WriteText("writetext.txt", var_s2, 1, 2, 3)
// Append 3 characters from the starting indext to the file
```

writetext.txt

```
1|  達明機器人Hi TM Robot機器人
```

```
? byte var_n1 = 100                    // Use decimal for values to convert to strings
File_WriteText("writetext2.txt", var_n1, 1)
```

writetext2.txt

```
1|  100
```

```
? int[] var_n4 = {10000, 20000, 80000}      // Use the "{, ,}" format for arrays
File_WriteText("writetext2.txt", var_n4, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}
```

```
// For other formats, use GetString() to convert to a stitng and write the string
? float var_n5 = 1.234
File_WriteText("writetext2.txt", var_n5, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}1.234
```

```
? double[] var_n8 = {1.23, -7.89}
File_WriteText("writetext2.txt", var_n8, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}1.234{1.23,-7.89}
```

```
? bool var_n9 = true
File_WriteText("writetext2.txt", var_n9, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}1.234{1.23,-7.89}true
```

```
? string var_n11 = "ABCDEFG"
File_WriteText("writetext2.txt", var_n11, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}1.234{1.23,-7.89}trueABCDEFG
```

```
? string[] var_n12 = {"ABC", "DEF", "達明機器人" }
  File_WriteText("writetext2.txt", var_n12, 1)
```

writetext2.txt

```
1|  100{10000,20000,80000}1.234{1.23,-7.89}trueABCDEFG{ABC,DEF,達明機器人}
```

7.8 File_WriteLine()

Put the data content in a string with newline characters (0x0D 0x0A) in the end and write to a file.

Syntax 1

bool **File_WriteLine**(
string,
?,
int,
int,
int
)

Parameter

string		File path
?		Values to write. Eligible for integers, floating-point numbers, Booleans, strings, or arrays.
int		Overwrite the file or append to the file.
	0	Over the file. If not existed, create a new file.
	1	Append to the file. If not existed, create a new file.
int		The starting index of the value to write (eligible for strings and arrays)
	0 .. length -1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int		The length of the value to write (eligible for strings and arrays)
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 2

bool **File_WriteLine**(
string,
?,
int,
int
)

Note

Same as Syntax 1. Set the length of the value to write to 0 writing up to the data ends.
File_WriteLine(string,?,int,int) => **File_WriteLine**(string,?,int,int,0)

Syntax 3

bool **File_WriteLine**(
string,
?,
int
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 writing up to the data ends.

File_WriteLine(string,?,int) => **File_WriteLine**(string,?,int,0,0)

Syntax 4

bool **File_WriteLine**(
string,
?
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 overwriting the file up to the data ends.

File_WriteLine(string,?) => **File_WriteLine**(string,?,0,0,0)

```
string var_s1 = "Hi TM Robot"
string var_s2 = "達明機器人"
bool var_flag = false
var_flag = File_WriteLine("writeline.txt", var_s2)
// Overwrite "達明機器人\u0D0A" to the file
```

```
writeline.txt
1|  達明機器人
2|
```

```
var_flag = File_WriteLine("writeline.txt", var_s1)
// Overwrite "Hi TM Robot\u0D0A" to the file
```

```
writeline.txt
1|  Hi TM Robot
2|
```

```
var_flag = File_WriteLine("writeline.txt", var_s2, 1)
// Append "達明機器人\u0D0A" to the file
```

```
writeline.txt
1|  Hi TM Robot
2|  達明機器人
3|
```

```
var_flag = File_WriteLine("writeline.txt", var_s1, 1, 3)
// Append "TM Robot\u0D0A" from the starting index 3 to the end to the file.
```

```
writeline.txt
1|  Hi TM Robot
2|  達明機器人
3|  TM Robot
4|
```

```
? byte[] var_n2 = {100, 200}        // The array uses the format {, ,}.
File_WriteLine("writeline2.txt", var_n2, 1)
```

```
writeline2.txt
1|  {100,200}
2|
```

```
// For other formats, use GetString() to convert to string and write.
? int var_n3 = 10000                // Convert the value in decimal to a string.
File_WriteLine("writeline2.txt", var_n3, 1)
```

```
writeline2.txt
1|  {100,200}
2|  10000
3|
```

? `float[] var_n6 = {1.23, 4.56, -7.89}`
File_WriteLine("writeline2.txt", var_n6, 1)

```
writeline2.txt
1|  {100,200}
2|  10000
3|  {1.23,4.56,-7.89}
4|
```

? `bool var_n9 = true`
File_WriteLine("writeline2.txt", var_n9, 1)

```
writeline2.txt
1|  {100,200}
2|  10000
3|  {1.23,4.56,-7.89}
4|  true
5|
```

? `string var_n11 = "ABCDEFG"`
File_WriteLine("writeline2.txt", var_n11, 1)

```
writeline2.txt
1|  {100,200}
2|  10000
3|  {1.23,4.56,-7.89}
4|  true
5|  ABCDEFG
6|
```

? `string[] var_n12 = {"ABC", "DEF", "達明機器人" }`
File_WriteLine("writeline2.txt", var_n12, 1)

```
writeline2.txt
1|  {100,200}
2|  10000
3|  {1.23,4.56,-7.89}
4|  true
5|  ABCDEFG
6|  {ABC,DEF,達明機器人}
7|
```

7.9 File_WriteLines()

Put the data content in a string array with newline characters (0x0D 0x0A) in the end and write to a file.

Syntax 1

bool **File_WriteLines**(
string,
?,
int,
int,
int
)

Parameter

string		File path
?		Values to write. Eligible for integers, floating-point numbers, Booleans, strings, or arrays.
int		Overwrite the file or append to the file.
	0	Over the file. If not existed, create a new file.
	1	Append to the file. If not existed, create a new file.
int		The starting index of the value to write (eligible for strings and arrays)
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int		The length of the value to write (eligible for strings and arrays)
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 2

bool **File_WriteLines**(
string,
?,
int,
int
)

Note

Same as Syntax 1. Set the length of the value to write to 0 writing up to the data ends.
File_WriteLines(string,?,int,int) => **File_WriteLines**(string,?,int,int,0)

Syntax 3

bool **File_WriteLines**(
string,
?,
int
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 writing up to the data ends.

File_WriteLines(string,?,int) => **File_WriteLines**(string,?,int,0,0)

Syntax 4

bool **File_WriteLines**(
string,
?
)

Note

Same as Syntax 1. Set the starting index and the length of the value to write to 0 overwriting the file up to the data ends.

File_WriteLines(string,?) => **File_WriteLines**(string,?,0,0,0)

* File_WriteText() : convert the data values to write to a string without adding newline characters in the end of the string.
File_WriteLine(): convert the data values to write to a string with adding newline characters in the end of the string.
File_WriteLines(): convert the data values to write to a string array with adding newline characters in the end of each element of the array.

```
string var_ss1 = {"Hi TM Robot", "達明機器人"}
bool var_flag = false
var_flag = File_WriteLines("writelines.txt", var_ss1)          // Overwrite ss1 to the file
```

writelines.txt

```
1|  Hi TM Robot
2|  達明機器人
3|
```

```
var_flag = File_WriteLines("writelines.txt", var_ss1, 1, 1)
// Append ss1 from the starting index 1 to the end to the file.
```

writelines.txt

```
1|  Hi TM Robot
2|  達明機器人
3|  Hi TM Robot
4|
```

? byte[] var_n2 = {100, 200}
File_WriteLines("writelines2.txt", var_n2, 1)

writelines2.txt

```
1|  100
2|  200
3|
```

? int var_n3 = 10000
File_WriteLines("writelines2.txt", var_n3, 1)

writelines2.txt

```
1|  100
2|  200
3|  10000
4|
```

? float[] var_n6 = {1.23, 4.56, -7.89}
File_WriteLines("writelines2.txt", var_n6, 1)

writelines2.txt

```
1|  100
2|  200
3|  10000
4|  1.23
5|  4.56
6|  -7.89
7|
```

? string var_n11 = "ABCDEFG"
File_WriteLines("writelines2.txt", var_n11, 1)

writelines2.txt

```
1|  100
2|  200
3|  10000
4|  1.23
5|  4.56
6|  -7.89
7|  ABCDEFG
8|
```

? string[] var_n12 = {"ABC", "DEF", "達明機器人" }
File_WriteLines("writelines2.txt", var_n12, 1)

writelines2.txt

```
 1| 100
 2| 200
 3| 10000
 4| 1.23
 5| 4.56
 6| -7.89
 7| ABCDEFG
 8| ABC
 9| DEF
10| 達明機器人
11|
```

7.10 File_Exists()

Check the file path for availability.

Syntax 1

bool **File_Exists**(
    string
)

Parameter

string	File path	

Return

bool	true	File path available
	false	File path unavailable
	*Return false file path unavailable for Voided file path without errors.	

Note

```
bool var_exists = false
var_exists = File_Exists("sampleFile1.txt")        // true
var_exists = File_Exists("sampleFileX.txt")        // false    // File path unavailable
var_exists = File_Exists("C:\SampleFile1.txt")     // false    // Void for absolute paths.
```

7.11 File_Length()

Check the file size.

Syntax 1

int **File_Length**(
string
)

Parameter

string	File path	

Return

int	In int32 data type. The maximum file size is limited to 2147483647 bytes.	
	-1	File path unavailable.
	-2	Exceeded the maximum file size limit.
	* Return -1 file path unavailable for void file path without errors.	

Note

```
Int var_len = 0
var_len = File_Length("sampleFile1.txt")          // 31
var_len = File_Length("sampleFileX.txt")          // -1  // File path unavailable
var_len = File_Length("C:\SampleFile1.txt")       // -1  // Void for absolute paths.
```

7.12 File_Delete()

Delete the file.

Syntax 1

bool **File_Delete**(
    string
    ...
)

Parameter

string	File path	
...	Available for multiple strings.	

Return

bool	true	Delete successfully. (Included unavailable or void file paths)
	false	Delete unsuccessfully. (Unable to delete the file for occupied)

Syntax 2

bool **File_Delete**(
    string[]
)

Parameter

string[]	File path

Return

bool	true	Delete successfully. (Included unavailable or void file paths)
	false	Delete unsuccessfully. (Unable to delete the file for occupied)

Note

```
bool var_flag = false
var_flag = File_Delete("sampleFile1.txt")            // true
var_flag = File_Delete("sampleFileX.txt")            // true      // File path unavailable
var_flag = File_Delete("C:\SampleFile1.txt")         // true      // Void for absolute paths.
var_flag = File_Delete("sampleFile1.txt", "sampleFileX.txt")
// Available for multiple file paths.
var_flag = File_Delete("sampleFile1.txt", "sampleFileX.txt", "C:\SampleFile1.txt")
// Available for multiple file paths.
string[] var_ss = {"sampleFile1.txt", "sampleFileX.txt", "C:\SampleFile1.txt""}
var_flag = File_Delete(var_ss)
var_flag = File_Delete(var_ss, "sampleFile2.txt") // Error. Void for syntax.
```

7.13 File_Copy()

Copy the file.

Syntax 1

bool **File_Copy**(
string,
string,
string
)

Parameter

string		Source file path
string		Target directory path
string		Target file name. Use the source file path equivalent for naming as the default if empty.

Return

bool	true	Copy successfully.
	false	Copy unsuccessfully.
	* Overwrite the target file if existed in the target path.	

Syntax 2

bool **File_Copy**(
string,
string
)

Note

Same as Syntax 1. Set the target file name with an empty string and use the source file path equivalent for naming.

File_Copy(string,string) => **File_Copy**(string,string,"")

```
File_Copy("sampleFile1.txt", ".\TextFiles", "s1.txt")
// copy .\TextFiles\sampleFile1.txt to .\TextFiles\s1.txt
File_Copy("sampleFile1.txt", ".\XmlFiles", "")
// copy .\TextFiles\sampleFile1.txt to .\XmlFiles\sampleFile1.txt
File_Copy("sampleFile1.txt", "\USB\TMROBOT", "s1.txt")
// copy .\TextFiles\sampleFile1.txt to USB\s1.txt
File_Copy("sampleFile1.txt", "\USB\TMROBOT")
// copy .\TextFiles\sampleFile1.txt to USB\sampleFile1.txt
bool var_flag = false
var_flag = File_Copy("sampleFile1.txt", "C:\folder")    // Error. Void for absolute paths.
var_flag = File_Copy("sampleFile1.txt", ".")
// Error. Neither TextFiles nor XmlFiles is in the file path.
```

7.14 File_CopyImage()

Copy the saved vision file.

Syntax 1

bool **File_CopyImage**(
string,
string,
string,
int
)

Parameters

string	Source saved vision file path	
string	Target directory path Granted to copy and save images to external paths such as external device path directories or remote path directories Not granted to copy and save the image to the local path such as ".\TextFiles" or ".\XmlFiles", and an error will be reported.	
string	Target file name. If the name is an empty string, the default files name is the same as the one in the source file path.	
int	Copy options	
	0	No error returned when failed to copy. No relative directory of the sourced image reserved. (default)
	1	No error returned when failed to copy. The relative directory of the sourced image reserved.
	2	An error returned when failed to copy. No relative directory of the sourced image reserved.
	3	An error returned when failed to copy. The relative directory of the sourced image reserved.

Return

bool	true	Copy successfully.
	false	Copy unsuccessfully.
	* If the file exists in the destination path, the destination file will be overwritten.	

Syntax 2

bool **File_CopyImage**(
string,
string,
string
)

Note

Same as syntax 1. Set the copy option to 0. No error returned when failed to copy. No relative directory of the sourced image reserved.
File_CopyImage(string,string,string) => **File_CopyImage**(string,string,string,0)

Syntax 3

bool **File_CopyImage**(

```
        string,
        string
    )
```

Note

Same as syntax 1. Set the target file name to an empty string and the same as the one in the source file path. Set the copy option to 0. No error returned when failed to copy. No relative directory of the sourced image reserved.

File_CopyImage(string,string) => **File_CopyImage**(string,string,"",0)

Syntax 4

```
bool File_CopyImage(
    string,
    string,
    int
)
```

Note

Same as syntax 1. Set the target file name to an empty string and the same as the one in the source file path.

File_CopyImage(string,string,int) => **File_CopyImage**(string,string,"",int)

```
var_bool flag = false
var_flag = File_CopyImage(Job1_ImagePath_TM, ".\TextFiles", "1.png")
// false // Copy to local directories not supported.
var_flag = File_CopyImage(Job1_ImagePath_TM, ".\XmlFiles", "1.png")
// false // Copy to local directories not supported.
var_flag = File_CopyImage(Job1_ImagePath_TM, ".\XmlFiles", "1.png", 2)
// false // Copy to local directories not supported.
var_flag = File_CopyImage(Job1_ImagePath_TM, "\USB\TMROBOT", "1.png")
// true // Copy Job1_ImagePath_TM (the vision AOI-only variable) to USB\1.png
var_flag = File_CopyImage(Job1_ImagePath_TM, "\USB\TMROBOT", "1.png", 3)
// true // Copy Job1_ImagePath_TM (the vision AOI-only variable) to
USB\ProjectName\Job1\Date\source\1.png
// Reserve the directory of the image to save.
var_flag = File_CopyImage(Job1_ImagePath_TM, "\USB\TMROBOT")
// true // Copy Job1_ImagePath_TM (the vision AOI-only variable) to USB\15-16-12_423.png
// Reserve the file name of the image to save.
var_flag = File_CopyImage(Job1_ImagePath_TM, "\USB\TMROBOT", 3)
// true // Copy Job1_ImagePath_TM (the vision AOI-only variable) to
USB\ProjectName\Job1\Date\source\15-16-12_423.png
// Reserve the directory and the file name of the image to save.
```

7.15 File_GetImage()

After executing a task job in TMvision, the system keeps the Source image storage path and the Result image storage path in the image storage path buffer. Users can use this function to retrieve the file path stored in the buffer and proceed to other operations such as copying it externally. This function takes priority to the oldest image storage path to get images (FIFO) and removes the path automatically later.

The maximum number of stored image paths in the buffer is 60. When a new image storage path to add to the buffer, if the capacity is insufficient, the oldest image storage path will be automatically removed from the butter, and the new image storage path will be automatically added to the buffer.

Syntax 1

string[] **File_GetImage**(
    int
)

Parameter

int Waiting time out to retrieve the image storage path
- < 0 Wait indefinitely until retrieved the image storage path. (default)
- = 0 Retrieve once.
- > 0 Time out after waiting for how much time (milliseconds)

Once using waiting, the process stays at this command until retrieved the image storage path or waiting timeout and keeps on the following executions

Return

string[] If SourceImage and ResultImage are empty strings, it denotes it does not retrieve any image storag path.
- [0] SourceImage Path
- [1] ResultImage Path
- [2] ResultData Path
- [1] JobName as the name of the vision job

Syntax 2

string[] **File_GetImage**(
)

Note

Same as syntax 1. Set the waiting to retrieve timeout to -1 as indefinitely waiting until retrieved the image storage path.

File_GetImage() => **File_GetImage**(-1)

```
string[] var_image = File_GetImage()          // Wait until retrieved the image storage path.
bool var_flag1 = File_CopyImage(var_image[0], "\USB\TMROBOT")
bool var_flag2 = File_CopyImage(var_image[1], "\USB\TMROBOT")
```

Syntax 3

string[] **File_GetImage**(
    string,
    int

)

Parameter

string The name of the vision job. Retrieve the job name-matched image storage path

int Waiting time out to retrieve the image storage path

< 0 Wait indefinitely until retrieved the image storage path. (default)

= 0 Retrieve once.

> 0 Time out after waiting for how much time (milliseconds)

Once using waiting, the process stays at this command until retrieved the image storage path or waiting timeout and keeps on the following executions

Return

string[] If SourceImage and ResultImage are empty strings, it denotes it does not retrieve any image storag path.

[0] SourceImage Path

[1] ResultImage Path

[2] ResultData Path

[1] JobName as the name of the vision job

Syntax 4

string[] **File_GetImage**(

string

)

Note

Same as syntax 3. Set the waiting to retrieve timeout to -1 as indefinitely waiting until retrieved the image storage path.

File_GetImage("Job1") **=>** **File_GetImage**("Job1", -1)

```
string[] var_image = File_GetImage("Job1")        // Wait until retrieved the image storage path.
bool var_flag1 = File_CopyImage(var_image[0], "\USB\TMROBOT")
bool var_flag2 = File_CopyImage(var_image[1], "\USB\TMROBOT")
```

7.16 File_Replace()

Replace and overwrite the string in the file with a specified string.

Syntax 1

bool **File_Replace**(
    string,
    string,
    string
)

Parameter

string	File path	
string	The string to be replaced	
string	The string to replace	

Return

bool	true	Success 1. The string to be replaced is empty. 2. The string to be replaced is absent. 3. The string to be replaced is found and overwritten in the file.
	false	Failure

Note

.\TextFiles\SampleFile6.txt

```
1|  6Hello World!
2|  6Hello TM Robot!
3|  6Hi TM Robot!
```

bool var_flag = false
var_flag = **File_Replace**("SampleFile6.txt", "Hello", "HI")

SampleFile6.txt

```
1|  6HI World!
2|  6HI TM Robot!
3|  6Hi TM Robot!
```

var_flag = **File_Replace**("SampleFile6.txt", "TM", "Techman")

SampleFile6.txt

```
1|  6HI World!
2|  6HI Techman Robot!
3|  6Hi Techman Robot!
```

var_flag = **File_Replace**("SampleFile6.txt", "6", "")

SampleFile6.txt

```
1|  HI World!
2|  HI Techman Robot!
3|  Hi Techman Robot!
```

7.17 File_GetToken()

Read the file by the string pattern and retrieve the substring in the string.

Syntax 1

string **File_GetToken**(
string,
string,
string,
int,
int
)

Parameter

string		File path
string		The prefix of the string to retrieve
string		The suffix of the string to retrieve
int		The number of the matched substring to retrieve
	>=1	Retrieve the nth matched substring
	-1	Retrieve the last matched substring
int		Remove options
	0	The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string	Return the retrieved string. Return the content of the string in the file if the prefix and the suffix are empty. Return an empty string if matching number <=0. If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 2

string **File_GetToken**(
string,
string,
string,
int
)

Note

Same as Syntax 1. Fill 0 for not removing the prefix and the suffix as the default.
File_GetToken(string,string,string,int) => **File_GetToken**(string,string,string,int,0)

Syntax 3

string **File_GetToken**(
string,
string,
string
)

Note

Same as Syntax 1. Fill 1 for the matching and 0 for not removing the prefix and the suffix as the default.

File_GetToken(string,string,string) => **File_GetToken**(string,string,string,1,0)

```
.\TextFiles\SampleFile7.txt
1|  $Hello World!
2|  $Hello TM Robot!
3|  $Hi TM Robot!$
```

```
string var_n = "SampleFile7.txt"
string var_s = ""
var_s = File_GetToken(var_n, "", "", 0)          // "$Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi
                                                 TM Robot!$"
var_s = File_GetToken(var_n, "$", "$")           // "$Hello World!\u0D0A$"
var_s = File_GetToken(var_n, "$", "$", 0)        // ""
var_s = File_GetToken(var_n, "$", "$", 1)        // "$Hello World!\u0D0A$"
var_s = File_GetToken(var_n, "$", "$", 2)        // "$Hi TM Robot!$"
var_s = File_GetToken(var_n, "$", "$", 3)        // ""
var_s = File_GetToken(var_n, "$", "$", 1, 1)     // "Hello World!\u0D0A"
var_s = File_GetToken(var_n, "$", "$", 2, 1)     // "Hi TM Robot!"
var_s = File_GetToken(var_n, "$", "", 1)         // "$Hello World!\u0D0A"
var_s = File_GetToken(var_n, "$", "", 2)         // "$Hello TM Robot!\u0D0A"
var_s = File_GetToken(var_n, "$", "", 3)         // "$Hi TM Robot!"
var_s = File_GetToken(var_n, "$", "", 4)         // "$"
var_s = File_GetToken(var_n, "", "$", 1)         // "$"
var_s = File_GetToken(var_n, "", "$", 2)         // "Hello World!\u0D0A$"
var_s = File_GetToken(var_n, "", "$", 3)         // "Hello TM Robot!\u0D0A$"
var_s = File_GetToken(var_n, "", "$", 4)         // "Hi TM Robot!$"
var_s = File_GetToken(var_n, "$", Ctrl("\r\n"), 1) // "$Hello World!\u0D0A"
var_s = File_GetToken(var_n, "$", newline, 2)      // "$Hello TM Robot!\u0D0A"
var_s = File_GetToken(var_n, "$", NewLine, 1, 1) // "Hello World!"
                                                 // Remove the prefix and the suffix
var_s = File_GetToken(var_n, Ctrl("\r\n"), "$", 1)         // "\u0D0A$"
var_s = File_GetToken(var_n, newline, "$", 2)              // "\u0D0A$"
var_s = File_GetToken(var_n, NewLine, "$", 1, 1) // ""
```

* \u0D0A denotes a new line character but not a string value.

```
.\TextFiles\SampleFile9.txt
1|  #Hello World!
2|  $Hello TM Robot!
3|  $Hi TM Robot!$
```

```
string var_n = "SampleFile9.txt"
string var_s = ""
var_s = File_GetToken(var_n, "", "")             // "#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi
                                                 TM Robot!$"
var_s = File_GetToken(var_n, "#", "")            // "#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi
                                                 TM Robot!$"
var_s = File_GetToken(var_n, "", "$")                      // "#Hello World!\u0D0A$"
var_s = File_GetToken(var_n, "#", newline, 1, 0)           // "#Hello World!\u0D0A"
var_s = File_GetToken(var_n, "#", newline, 1, 1)           // "Hello World!"
var_s = File_GetToken(var_n, "#", newline, 1, 2)           // "#Hello World!\u0D0A"
```

```
var_s = File_GetToken(var_n, "#", newline, 1, 3)        // "Hello World!"
var_s = File_GetToken(var_n, "$", newline, 1, 0)        // "$Hello TM Robot!\u0D0A"
var_s = File_GetToken(var_n, "$", newline, 1, 2)        // ""
                                                        // $ not in the start of the file. Return an empty string.
var_s = File_GetToken(var_n, "$", "", 1, 2)             // ""
                                                        // $ not in the start of the file. Return an empty string.
var_s = File_GetToken(var_n, "#", "", 1, 2)             // "#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi
                                                        TM Robot!$"
var_s = File_GetToken(var_n, "", "$", 1, 2)             // "#Hello World!\u0D0A$"
var_s = File_GetToken(var_n, "", "$", -1, 2)            // "Hi TM Robot!$"
var_s = File_GetToken(var_n, "", "$", 100, 2)       // ""          // Exceeded the matching number
var_s = File_GetToken(var_n, "", "#", 1, 2)             // "#"
```

Syntax 4

```
string File_GetToken(
    string,
    byte[],
    byte[],
    int,
    int
)
```

Parameter

string		File path
byte[]		The prefix of the string to retrieve in the byte array
byte[]		The suffix of the string to retrieve in the byte array
int		The number of the matched substring to retrieve
	>=1	Retrieve the nth matched substring
	-1	Retrieve the last matched substring
int		Remove options
	0	The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string — Return the retrieved string.

Return the content of the string in the file if the prefix and the suffix are empty.

Return an empty string if matching number <=0.

If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 5

```
string File_GetToken(
    string,
    byte[],
    byte[],
    int
)
```

Note

Same as Syntax 4. Fill 0 for not removing the prefix and the suffix as the default.

File_GetToken(string,byte[],byte[],int) => **File_GetToken**(string,byte[],byte[],int,0)

Syntax 6

string **File_GetToken**(
string,
byte[],
byte[]
)

Note

Same as Syntax 4. Fill 1 for the matching and 0 for not removing the prefix and the suffix as the default.

File_GetToken(string,byte[],byte[]) => **File_GetToken**(string,byte[],byte[],1,0)

```
.\TextFiles\SampleFile8.txt
1|  $Hello World!
2|  Hello$ TM Robot!
3|  Hi$ TM Robot!$
```

```
string var_n = "SampleFile8.txt", var_s = ""
byte[] var_bb0 = {}, var_bb1 = {0x24}, var_bb2 = {0x0D, 0x0A}
// 0x24 is $   and   0x0D 0x0A is \u0D0A
var_s = File_GetToken(var_n, bb0, bb0, 0)
// "$Hello World\u0D0AHello$ TM Robot!\u0D0AHi$ TM Robot!$"
var_s = File_GetToken(var_n, bb1, bb1)          // "$Hello World\u0D0AHello$"
var_s = File_GetToken(var_n, bb1, bb1, 0)       // ""
var_s = File_GetToken(var_n, bb1, bb1, 1)       // "$Hello World\u0D0AHello$"
var_s = File_GetToken(var_n, bb1, bb1, 2)       // "$ TM Robot!$"
var_s = File_GetToken(var_n, bb1, bb1, 3)       // ""
var_s = File_GetToken(var_n, bb1, bb1, 1, 1)    // "Hello World\u0D0AHello"
var_s = File_GetToken(var_n, bb1, bb1, 2, 1)    // " TM Robot!"
var_s = File_GetToken(var_n, bb1, bb0, 1)       // "$Hello World\u0D0AHello"
var_s = File_GetToken(var_n, bb1, bb0, 2)       // "$ TM Robot!\u0D0AHi"
var_s = File_GetToken(var_n, bb1, bb0, 3)       // "$ TM Robot!"
var_s = File_GetToken(var_n, bb1, bb0, 4)       // "$"
var_s = File_GetToken(var_n, bb0, bb1, 1)       // "$"
var_s = File_GetToken(var_n, bb0, bb1, 2)       // "Hello World\u0D0AHello$"
var_s = File_GetToken(var_n, bb0, bb1, 3)       // " TM Robot!\u0D0AHi$"
var_s = File_GetToken(var_n, bb0, bb1, 4)       // " TM Robot!$"
var_s = File_GetToken(var_n, bb1, bb2, 1)       // "$Hello World\u0D0A"
var_s = File_GetToken(var_n, bb1, bb2, 2)       // "$ TM Robot!\u0D0A"
var_s = File_GetToken(var_n, bb1, bb2, 1, 1)    // "Hello World"
                                                // Remove the prefix and the suffix
var_s = File_GetToken(var_n, bb2, bb1, 1)       // "\u0D0AHello$"
var_s = File_GetToken(var_n, bb2, bb1, 2)       // "\u0D0AHi$"
var_s = File_GetToken(var_n, bb2, bb1, 1, 1)    // "Hello"
```

* \u0D0A denotes a new line character but not a string value.

7.18 File_GetAllTokens()

Read the file by the string pattern and retrieve all eligible substrings.

Syntax 1

string[] **File_GetAllTokens**(
string,
string,
string,
int
)

Parameter

string		File path
string		The prefix of the string to retrieve
string		The suffix of the string to retrieve
int		Remove options
	0	The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)
	1	The 1st matched not in the start of the input string, and remove the prefix and the suffix.
	2	The 1st matched in the start of the input string, and not remove the prefix and the suffix.
	3	The 1st matched in the start of the input string, and remove the prefix and the suffix.

Return

string[] Return the eligible string in an array.
Return the content of the string in the file as a string array if the prefix and the suffix are empty.
If the remove option is 2 or 3, the first match retrieved must be at the start of the input string; otherwise, it returns an empty string.

Syntax 2

string[] **File_GetAllTokens**(
string,
string,
string
)

Note

Same as Syntax 1. Fill 0 for not removing the prefix and the suffix as the default.
File_GetAllTokens(string,string,string) => **File_GetAllTokens**(string,string,string,0)

```
.\TextFiles\SampleFile7.txt
1|  $Hello World!
2|  $Hello TM Robot!
3|  $Hi TM Robot!$
```

```
string var_n = "SampleFile7.txt"
string[] var_ss = {}
var_ss = File_GetAllTokens(var_n, "", "")     // {"$Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM
                                              Robot!$"}
var_ss = File_GetAllTokens(var_n, "$", "$") // {"$Hello World!\u0D0A$", "$Hi TM Robot!$"}
var_ss = File_GetAllTokens(var_n, "$", "$", 1)    // {"Hello World!\u0D0A", "Hi TM Robot!"}
var_ss = File_GetAllTokens(var_n, "$", "", 1)
// {"Hello World!\u0D0A", "Hello TM Robot!\u0D0A", "Hi TM Robot!", ""}
```

.\TextFiles\SampleFile9.txt

```
1|  #Hello World!
2|  $Hello TM Robot!
3|  $Hi TM Robot!$
```

```
string var_n = "SampleFile9.txt"
string[] var_ss = {}
var_ss = File_GetAllTokens(var_n, "", "")
// {"#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM Robot!$"}
var_ss = File_GetAllTokens(var_n, "$", "$", 0)    // {"$Hello TM Robot!\u0D0A$"}
var_ss = File_GetAllTokens(var_n, "$", "$", 1)    // {"Hello TM Robot!\u0D0A"}
var_ss = File_GetAllTokens(var_n, "$", "$", 2)    // {}
var_ss = File_GetAllTokens(var_n, "$", "$", 3)    // {}
var_ss = File_GetAllTokens(var_n, "$", "", 0)
// {"$Hello TM Robot!\u0D0A", "$Hi TM Robot!", "$"}
var_ss = File_GetAllTokens(var_n, "$", "", 2)     // {}
var_ss = File_GetAllTokens(var_n, "#", "", 0)
// {"#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM Robot!$"}
var_ss = File_GetAllTokens(var_n, "#", "", 1)
// {"Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM Robot!$"}
var_ss = File_GetAllTokens(var_n, "#", "", 2)
// {"#Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM Robot!$"}
var_ss = File_GetAllTokens(var_n, "#", "", 3)
// {"Hello World!\u0D0A$Hello TM Robot!\u0D0A$Hi TM Robot!$"}
```

7.19 File_GetFiles()

Retrieve file names in the assigned directory.

Syntax 1

```
string[] File_GetFiles(
    string,
    string,
    int
)
```

Parameter

string	The assigned directory
string	The string to be searched in the file name is case-insensitive. A search is considered valid even if the string is empty.
int	Retrieving options
0	Retrieve the file names in the specified directory only.
1	Retrieve the file names in the specified directory and all its subdirectories.

Return

string[]	Return the file name with the path associated with the assigned directory,such as assigned .\TextFiles as the directory.

```
[0] "Text1.txt"             // ".\TextFiles\Text1.txt"
[1] "Folder2\Text2.txt"     // ".\TextFiles\Folder2\Text2.txt"
```

Syntax 2

```
string[] File_GetFiles(
    string,
    string
)
```

Note

Same as Syntax 1, with 0 as the default retrieving option.

Syntax 3

```
string[] File_GetFiles(
    string
)
```

Note

Same as Syntax 1, with 0 as the default retrieving option and an empty string set to search in the filename.

Note

Supposed that files in the directory \TextFiles are
Text1.txt
Folder2\Text2.txt

```
File_GetFiles(".\TextFiles", "", 0)                 // {"Text1.txt"}
File_GetFiles(".\TextFiles", "", 1)                 // {"Text1.txt", "Folder2\Text2.txt"}
File_GetFiles(".\TextFiles", "Text1.txt", 1)        // {"Text1.txt"}
File_GetFiles(".\TextFiles", "Text2.txt")           // {}
File_GetFiles(".\TextFiles", "Text2.txt", 1)        // {"Folder2\Text2.txt"}
File_GetFiles(".\TextFiles")                        // {"Text1.txt"}
```

Supposed that files in the directory \\127.0.0.1\shared are

PN-2024-07-07.log
Image1.png
Text1.txt
Folder2\Image1.png
Folder2\Text2.txt

```
File_GetFiles("\\127.0.0.1\shared", "", 0)
// {"PN-2024-07-07.log", "Image1.png", "Text1.txt"}
File_GetFiles("\\127.0.0.1\shared", "", 1)
// {"PN-2024-07-07.log", "Image1.png", "Text1.txt", "Folder2\Image1.png", "Folder2\Text2.txt"}

File_GetFiles("\\127.0.0.1\shared", "image1.png", 0)
// {"Image1.png"}       // case-insensitive
File_GetFiles("\\127.0.0.1\shared", "image1.png", 1)
// {"Image1.png", "Folder2\Image1.png"}

File_GetFiles("\\127.0.0.1\shared", "*.txt", 1) // {"Text1.txt", "Folder2\Text2.txt"}
File_GetFiles("\\127.0.0.1\shared", "*.txt")    // {"Text1.txt"}
```

7.20 File_LogWrite()

Write the log file that messages are available on the view page of the flowchart.

Syntax 1

bool **File_LogWrite**(
string,
string,
string,
string, ...
)

Parameter

string	The device to write
string	The directory to write
string	Title
string	Content

*Titles and content can be multiple.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 2

bool **File_LogWrite**(
string,
string
)

Parameter

string	Title
string	Content

* The system will use the device and directory settings from the previous execution of Syntax 1. No file writing if there is no previous execution of Syntax 1, but the information will still appear on the view page of the flowchart.

Return

bool	true	Write successfully.
	false	Write unsuccessfully.

Syntax 3

bool **File_LogWrite**(
string
)

Parameter

string Content
* The system will use the device and directory settings from the previous execution of Syntax 1. No file writing if there is no previous execution of Syntax 1, but the information will still appear on the view page of the flowchart.

Return

bool true Write successfully.
false Write unsuccessfully.

```
File_LogWrite("text0")      // false. Write unsuccessfully for no previous execution of Syntax 1,

File_LogWrite("\USB\TMROBOT", "aaa", "title1", "text1")
// Output log file to \USB\TMROBOT\aaa\ProjectName-yyyy-MM-dd.log
// dd/MM/yyyy HH:mm:ss title1=text1
File_LogWrite("\USB\TMROBOT", "aaa", "title2", "text2", "title3", "text3")
// Output log file to \USB\TMROBOT\aaa\ProjectName-yyyy-MM-dd.log
// dd/MM/yyyy HH:mm:ss title2=text2
// dd/MM/yyyy HH:mm:ss title3=text3

File_LogWrite("\USB\TMROBOT", "aaa", "title4")
// dd/MM/yyyy HH:mm:ss title4
File_LogWrite("\USB\TMROBOT", "aaa")          // Will execute by syntax 2.
// dd/MM/yyyy HH:mm:ss \USB\TMROBOT=aaa
File_LogWrite("title5", "text5")
// dd/MM/yyyy HH:mm:ss title5=text5
File_LogWrite("text6")
// dd/MM/yyyy HH:mm:ss text6
```

8. Serial Port Functions

8.1 *SerialPort Class*

Use SerialPort class and declare variables to create a COM port device. The variable name will be the device name.

Construct 1

SerialPort *VariableName* = string, int, string, int, float, int, bool, bool, bool
SerialPort *VariableName* = string, int, string, int, float, int
SerialPort *VariableName* = string, int, string, int, float
SerialPort *VariableName* = string, int

Parameter

string	connection description		
int	bits per second, BaudRate		
string	parity check	"none", "odd", "even", "mark", "space"	("none" by default)
int	Data Bits	5, 6, 7, 8	(8 by default)
float	Stop Bits	1, 1.5, 2	(1 by default)
int	read/write timeout in millisecond	0 .. 10000	(10000 ms by default)
bool	DTR/DSR	true, false	(false by default)
bool	RTS/CTS	true, false	(false by default)
bool	XON/XOFF	true, false	(false by default)

Note

```
SerialPort spd_c1 = "COM2",115200
  // construct a device, with Baudrate 115200
SerialPort spd_c2 = "COM2",115200,"none",8,1
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1
SerialPort spd_c3 = "COM2",115200,"none",8,1,10000
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1, Timeout 10000ms
```

- In a flow project, it will create a device from the serial port list and connect to it actively.
- In a script project, after creating a device by the syntax content, it will not connect to the device. It takes the open device function to connect.
- Whether using the device to read or write, it will ask for confirmation of connecting to the device.

8.2 *com_open()*

Open a Serial Port device.

Syntax 1

bool **com_open**(
    string
)

Parameter

string	Serial Port device name	

Return

bool	True	Open successfully.
	False	Open unsuccessfully. (The project reports error.)

Note

```
SerialPort spd_dev = "COM2",115200
com_open("spd_dev")
```

8.3 *com_close()*

Close a Serial Port device.

Syntax 1

bool **com_close**(
    string
)

Parameter

string		Serial Port device name

Return

bool	True	Close successfully.
	False	Close unsuccessfully.

Note

```
SerialPort spd_dev = "COM2",115200
com_open("spd_dev")
com_close("spd_dev")
```

When the project starts running as going from the start node, it opens the serial port for connections and receives the data from the serial port consistently. For data received in the received buffer, users can use the function com_read to read data in the buffer.

Once opened the Serial Port, it receives data from it continuously and puts them in the receiving buffer. Users can use the function com_read or associatd functions to get data from the buffer. When the project stops running, it closes the opened Serial Port and clears the receiving buffer.

The receiving buffer comes with a capacity limitation. If there is data coming to the buffer and the buffer is out of space, it removes the earliest data automatically for the latest data coming into the buffer.

8.4 *com_read()*

Read data in the Serial Port received buffer and return an array byte[].

Syntax 1

byte[] **com_read**(
    string
)

Parameters

string The name of the device on the Serial Port

Return

byte[] Return all the data content. If the content is empty, it returns byte[0].

Note

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
byte[] value = com_read("spd")
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // ReceivedBuffer = {}
```

*This function reads all data in the received buffer and clears the received buffer.

Syntax 2

byte[] **com_read**(
    string,
    int,
    int
)

Parameters

string The name of the device on the Serial Port

int The number of the elements to read (based on the length of byte[])

- <= 0 Read all elements
- > 0 Read a specified number of the elements (Data is available when the specified number fulfills.)

int The length of time to read in millisecond

- <= 0 Read once only

> 0 Read many times until there is data or the time is up.

Return

byte[] Return the specified number of the elements with byte[]. If the elements is insufficient, it returns byte[0].

Syntax 3

byte[] **com_read**(
string,
int
)

Note

The syntax is the same as syntax 2. The default length of time to read is 0.

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
value = com_read("spd", 6)
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C}
  // ReceivedBuffer = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
value = com_read("spd", 100)
  // value byte[] = {}
  // Insufficient elements for no more than 100 elements in the received buffer and return byte[0].
  // ReceivedBuffer = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
value = com_read("spd", 0)
  // value byte[] = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A} // Read all elements
  // ReceivedBuffer = {}
value = com_read("spd", 4, 100)
  // value byte[] = {}
  // Insufficient elements for no more than 4 elements in the received buffer and return byte[0].
  // But the length of time to read is set to 100 ms, the process stays in the function until there is data or
 the time is up and exits the function.
  // ReceivedBuffer = {0x31,0x32,0x33,0x34,0x35,0x36,0x37,0x38}
  // Supposed it receives data after 50ms,
  // value byte[] = {0x31,0x32,0x33,0x34}   // it reads 4 element and exits the function.
  // ReceivedBuffer = {0x35,0x36,0x37,0x38}
```

Syntax 4

byte[] **com_read**(
string,
byte[] or string,
byte[] or string,
int,
int
)

Parameters

string The name of the device on the Serial Port

byte[] or string
Terms of the prefix to read. If the input is byte[0] or "", an empty string, it means no prefix terms.

byte[] or string
Terms of the suffix to read. If the input is byte[0] or "", an empty string, it means no suffix terms.

int Remove options
- 0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)
- 1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.
- 2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.
- 3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

int The length of time to read in millisecond
- <= 0 Read once only
- > 0 Read many times until there is data or the time is up.

Return

byte[] Return with byte[] in the first matched terms of the prefix and the suffix.
It retrieves data with the content matches the first of all terms, and the rest will be reserved and not retrieved.
If there is no match, it returns byte[0].

Syntax 5

```
byte[] com_read(
    string,
    byte[] or string,
    byte[] or string,
    int
)
```

Note

The syntax is the same as syntax 4. The default length of time to read is 0.

Syntax 6

```
byte[] com_read(
    string,
    byte[] or string,
    byte[] or string
)
```

Note

The syntax is the same as syntax 4. The default is not to remove the prefix and the suffix from the read content and the length of time to read is 0.

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
value = com_read("spd", "He", newline) // prefix "He", suffix \u0D0A
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}       // Hello,\u0D0A
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // retrieve the first match and reserve the rest
value = com_read("spd", "", newline, 1) // prefix "", suffix \u0D0A. Remove both the prefix and the
  suffix.
  // value byte[] = {0x57,0x6F,0x72,0x6C,0x64}          // World
  // ReceivedBuffer = {}
value = com_read("spd", "", newline, 1, 100)
  // prefix "", suffix \u0D0A. Remove both the prefix and the suffix. The length of time to read is 100ms.
  // value byte[] = {}
  // No matched terms to read. Read byte[0]. Wait for 100 ms.
  // ReceivedBuffer = {}
```

```
  // ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C}
  // ReceivedBuffer = {}

ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
value = com_read("spd", "lo", newline)  // prefix "lo", suffix \u0D0A
  // value byte[] = {0x6C,0x6F,0x2C,0x0D,0x0A}              // lo,\u0D0A
  // The data before the first matched term, {0x48,0x65,0x6C}, will be removed.
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // retrieve the first match and reserve the rest
byte[] bb = {}
value = com_read("spd", bb, newline)                      // prefix byte[0], suffix \u0D0A
  // value byte[] = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}       // World\u0D0A
  // ReceivedBuffer = {}
value = com_read("spd", bb, newline, 0, 100)      // prefix byte[0], suffix \u0D0A, 100ms
  // value byte[] = {}
  // No matched terms to read. Read byte[0]. Wait for 100 ms.
  // ReceivedBuffer = {}
  // ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // ReceivedBuffer = {}

ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,      // $Hello
                  0x23,0x48,0x69,0x0D,0x0A,                     // #Hi
                  0x24,0x54,0x4D,0x0D,0x0A,                     // $TM
                  0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}      // #Robot
value = com_read("spd", "#", newline, 2)            // prefix "#" suffix \u0D0A
  // value byte[] = {}                              // # not in the start. Return an empty array.
  // ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,0x23,0x48,0x69,0x0D,0x0A,
                       0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read("spd", "$", newline, 2)            // prefix "$" suffix \u0D0A
  // value byte[] = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A}
  // It must be in the start to retrieve the first match.
  // ReceivedBuffer = {0x23,0x48,0x69,0x0D,0x0A,
                       0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read("spd", "#", newline, 2)            // prefix "#" suffix \u0D0A
  // value byte[] = {0x23,0x48,0x69,0x0D,0x0A}              // It must be in the start to retrieve the first
  match.
  // ReceivedBuffer = {0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read("spd", "$", newline, 3)            // prefix "$" suffix \u0D0A
  // value byte[] = {0x54,0x4D}
  // ReceivedBuffer = {0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read("spd", "#", newline, 3)            // prefix "#" suffix \u0D0A
  // value byte[] = {0x52,0x6F,0x62,0x6F,0x74}
  // ReceivedBuffer = {}
```

Syntax 7

byte[] **com_read**(
string,
byte[] or string,
int,
int
)

Parameters

string The name of the device on the Serial Port

byte[] or string
Terms of the suffix to read. If the input is byte[0] or "", an empty string, it means no suffix terms.

int Remove options
- 0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)
- 1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.
- 2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.
- 3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

int The length of time to read in millisecond
- <= 0 Read once only
- > 0 Read many times until there is data or the time is up.

* No terms of the prefix to read.

Return

byte[] Return with byte[] in the first matched terms of the prefix and the suffix.
It retrieves data with the content matches the first of all terms, and the rest will be reserved and not retrieved.
If there is no match, it returns byte[0].

Syntax 8

byte[] **com_read**(
string,
byte[] or string,
int
)

Note

The syntax is the same as syntax 7. The default length of time to read is 0.

Syntax 9

byte[] **com_read**(
string,
byte[] or string
)

Note

The syntax is the same as syntax 7. The default is not to remove the prefix and the suffix from the read content and the length of time to read is 0.

Note

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
value = com_read("spd", newline)   // suffix \u0D0A
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}       // Hello,\u0D0A
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
```

```
  // retrieve the first match and reserve the rest
value = com_read("spd", newline)  // suffix \u0D0A
  // value byte[] = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}        // World\u0D0A
  // ReceivedBuffer = {}

ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
value = com_read("spd", newline, 1)                // suffix \u0D0A
  // value byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C}        // Hello,
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // retrieve the first match and reserve the rest
value = com_read("spd", newline, 1)                // suffix \u0D0A
  // value byte[] = {0x57,0x6F,0x72,0x6C,0x64}              // World
  // ReceivedBuffer = {}
value = com_read("spd", newline, 1, 100)           // suffix \u0D0A, 100ms
  // value byte[] = {}
  // No matched terms to read. Read byte[0]. Wait for 100 ms.
  // ReceivedBuffer = {}
  // ReceivedBuffer = {0x31,0x32,0x33,0x34,0x35,0x36,0x0D,0x0A}
  // value byte[] = {0x31,0x32,0x33,0x34,0x35,0x36}
  // ReceivedBuffer = {}
```

8.5 *com_read_string()*

Read the data in the Serial Port buffer, and convert the data to a UTF8 string.

Syntax 1

string **com_read_string**(
    string
)

Parameters

string	The name of the device on the Serial Port

Return

string	Return all the data content. If the content is empty, it returns an empty string.

Syntax 2

string **com_read_string**(
    string,
    int,
    int
)

Parameters

string	The name of the device on the Serial Port
int	The number of characters to read (based on the number of characters of the string)
<= 0	Read all characters
> 0	Read a specified number of the characters (Data is available when the specified number fulfills.)
int	The length of time to read in millisecond
<= 0	Read once only
> 0	Read many times until there is data or the time is up.

Return

string	Returns the specified number of characters as a string. If the characters are insufficient, it returns an empty string.

Syntax 3

string **com_read_string**(
    string,
    int
)

Note

The syntax is the same as syntax 2. The default length of time to read is 0.

Syntax 4

string **com_read_string**(
    string,
    byte[] or string,
    byte[] or string,
    int,
    int
)

Parameters

string The name of the device on the Serial Port

byte[] or string
Terms of the prefix to read. If the input is byte[0] or "", an empty string, it means no prefix terms.

byte[] or string
Terms of the suffix to read. If the input is byte[0] or "", an empty string, it means no suffix terms.

int Remove options

0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)

1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.

2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.

3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

int The length of time to read in millisecond

<= 0 Read once only

> 0 Read many times until there is data or the time is up.

Return

string It retrieves data with the content matches the first of all terms
It retrieves data with the content matches the first of all terms, and the rest will be reserved and not retrieved.
If there is no match, it returns an empty string.

Syntax 5

```
string com_read_string(
    string,
    byte[] or string,
    byte[] or string,
    int
)
```

Note

The syntax is the same as syntax 4. The default length of time to read is 0.

Syntax 6

```
string com_read_string(
    string,
    byte[] or string,
    byte[] or string
)
```

Note

The syntax is the same as syntax 4. The default is not to remove the prefix and the suffix from the read content and the length of time to read is 0.

Syntax 7

```
string com_read_string(
    string,
    byte[] or string,
    int,
    int
)
```

Parameters

string The name of the device on the Serial Port

byte[] or string
Terms of the suffix to read. If the input is byte[0] or "", an empty string, it means no suffix terms.

int Remove options

0 The 1st matched not in the start of the input string, and not remove the prefix and the suffix. (default)

1 The 1st matched not in the start of the input string, and remove the prefix and the suffix.

2 The 1st matched in the start of the input string, and not remove the prefix and the suffix.

3 The 1st matched in the start of the input string, and remove the prefix and the suffix.

int The length of time to read in millisecond

<= 0 Read once only

> 0 Read many times until there is data or the time is up.

* No terms of the prefix to read.

Return

string Returns as a string with the first matched terms of the prefix and the suffix.
Retrieves data in the content matches to the first of all terms, and the rest will be reserved and not retrieved.
If there is no match, it returns an empty string.

Syntax 8

```
string com_read_string(
    string,
    byte[] or string,
    int
)
```

Note

The syntax is the same as syntax 7. The default length of time to read is 0.

Syntax 9

```
string com_read_string(
    string,
    byte[] or string
)
```

Note

The syntax is the same as syntax 7. The default is not to remove the prefix and the suffix from the read content and the length of time to read is 0.

Note

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
string value = com_read_string("spd")
  // value string = "Hello, World\u0D0A"
  // ReceivedBuffer = {}
```

ReceivedBuffer = {0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}

```
value = com_read_string("spd", 4)
```

```
    // value string = "TM 達明"      // {0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E}
    // Retrieve 4 characters based on the length of the string.
    // var _ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
  value = com_read_string("spd", 5, 100)
    // value string = ""
    // Insufficient characters for no more than 5 characters in the received buffer based on the length of the
    string. Wait for 100 ms.
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA, 0x0D, 0x0A}
    // value string = "機器人\u0D0A"
    // ReceivedBuffer = {}

  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  value = com_read_string("spd", "He", newline)   // prefix "He", suffix \u0D0A
    // value string = "Hello,\u0D0A"
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}   // retrieve the first match and reserve the
    rest
  value = com_read_string("spd", "", newline, 1)
    // prefix "", suffix \u0D0A. Remove both the prefix and the suffix.
    // value string = "World"
    // ReceivedBuffer = {}
  value = com_read_string("spd", "", newline, 1, 100)
    // value string = ""              // No matched terms to read. Read an empty string. Wait for 100 ms.
    // ReceivedBuffer = {}
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA, 0x0D, 0x0A}
    // value string = "機器人"

  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  value = com_read_string("spd", "lo", newline)    // prefix "lo", suffix \u0D0A
    // value string = "lo,\u0D0A"
    // The data before the first matched term, "Hel", will be removed.
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
    // retrieve the first match and reserve the rest
  value = com_read_string("spd", newline, 1) // suffix \u0D0A
    // value string = "World"
    // ReceivedBuffer = {}

  ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,     // $Hello
                    0x23,0x48,0x69,0x0D,0x0A,                    // #Hi
                    0x24,0x54,0x4D,0x0D,0x0A,                    // $TM
                    0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}     // #Robot

  value = com_read_string("spd", "#", newline, 2)       // prefix "#" suffix \u0D0A
    // value string = ""                                // # not in the start. Return an empty array.
    // ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,0x23,0x48,0x69,0x0D,0x0A,
                         0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
```

```
value = com_read_string("spd", "$", newline, 2)          // prefix "$" suffix \u0D0A
  // value string = "$Hello\u0D0A"                        // It must be in the start to retrieve the first
  match.
  // ReceivedBuffer = {0x23,0x48,0x69,0x0D,0x0A,
                       0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read_string("spd", "#", newline, 2)          // prefix "#" suffix \u0D0A
  // value string = "#Hi\u0D0A"                          // It must be in the start to retrieve the first match.
  // ReceivedBuffer = {0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}

value = com_read_string("spd", "$", newline, 3)          // prefix "$" suffix \u0D0A
  // value string = "TM"
  // ReceivedBuffer = {0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
value = com_read_string("spd", "#", newline, 3)          // prefix "#" suffix \u0D0A
  // value string = "Robot"
  // ReceivedBuffer = {}
ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64}
value = com_read_string("spd", newline)                  // suffix \u0D0A
  // value string = "Hello,\u0D0A"
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}     // retrieve the first match and reserve the rest
value = com_read_string("spd", newline, 0) // suffix \u0D0A
  // value string = ""                                   // No matched terms to read. Read an empty string.
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}
value = com_read_string("spd", newline, 1, 100)// suffix \u0D0A
  // value string = ""
  // No matched terms to read. Read an empty string. Wait for 100 ms.
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A,0x31,0x32,0x33,0x0D,0x0A}
  // value string = "World"
  // ReceivedBuffer = {0x31,0x32,0x33,0x0D,0x0A}     // retrieve the first match and reserve the rest
value = com_read_string("spd", newline, 2) // suffix \u0D0A
  // value string = "123\u0D0A"
  // ReceivedBuffer = {}
```

8.6 *com_write()*

Write data to the Serial Port

Syntax 1

bool **com_write**(
string,
?,
int,
int
)

Parameters

string	The name of the device on the Serial Port	
?	The value to write. Available types: int, float, , bool, string, and array. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.	
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

Boo l	True	write successfully
	False	write unsuccessfully 1. The value to write is an empty string or an empty array. 2. Unable to send to the serial port correctly.

Syntax 2

bool **com_write**(
string,
?,
int
)

Note

The syntax is the same as syntax 1. The default length of data to write is 0.

.

Syntax 3

bool **com_write**(
string,
?
)

Note

The syntax is the same as syntax 1. The starting index for the data value to write is 0. The default length of data to write is 0.

```
flag = com_write("spd", 100)          // write 0x64
flag = com_write("spd", 1000)         // write 0xE8 0x03 0x00 0x00 (int, Little Endian)
flag = com_write("spd", (float)1.234)     // write 0xB6 0xF3 0x9D 0x3F (float, Little Endian)
flag = com_write("spd", (double)123.456)
  // write 0x77 0xBE 0x9F 0x1A 0x2F 0xDD 0x5E 0x40 (double, Little Endian)
flag = com_write("spd", "Hello, World"+newline)
  // write 0x48 0x65 0x6C 0x6C 0x6F 0x2C 0x20 0x57 0x6F 0x72 0x6C 0x64 0x0D 0x0A (string, UTF8)
flag = com_write("spd", 1000, 1, 2) //Invalid in the value, the starting index, and the length
  // write 0xE8 0x03 0x00 0x00 (int, Little Endian)

byte[] bb = {100, 200}
flag = com_write("spd", bb)           // write 0x64 0xC8
flag = com_write("spd", bb, 1, 1)     // write 0xC8
// Array. Retrieve 1 element from the index 1. [1]=200
flag = com_write("spd", bb, -1, 1)    // write 0x64
// Array. Retrieve 1 element from the index 0. [0]=100
flag = com_write("spd", "達明機器人", 2)
// String. Retrieve from the index 2 until the index ends. "機器人"
// write 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA (string, UTF8)
string[] ss = {"TM", "", "達明機器人" }
flag = com_write("spd", ss)
  // write 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
flag = com_write("spd", Byte_Concat(GetBytes(ss), GetBytes(newline)))
  // write 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
  0x0D 0x0A
flag = com_write("spd", ss, 2, 100)
  // Array. Retrieve 100 elements (to the end) from the index 2. [2]=達明機器人
  // write 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
```

8.7 *com_writeline()*

Write data to the Serial Port and add line break symbols, 0x0D 0x0A, in the end of the data automatically

Syntax 1

bool **com_writeline**(
string,
?,
int,
int
)

Parameters

string	The name of the device on the Serial Port	
?	The value to write. Available types: int, float, , bool, string, and array. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.	
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

bool	True	write successfully
	False	write unsuccessfully 1. The value to write is an empty string or an empty array. 2. Unable to send to the serial port correctly.

Syntax 2

bool **com_writeline**(
string,
?,
int,
)

Note

The syntax is the same as syntax 1. The default length of data to write is 0.

Syntax 3

bool **com_writeline**(
string,
?,
)

Note

The syntax is the same as syntax 1. The default starting index of the data to write is 0.

The default length of data to write is 0.

```
flag = com_writeline("spd", 100)          // write 0x64 0x0D 0x0A
flag = com_writeline("spd", 1000)         // write 0xE8 0x03 0x00 0x00 0x0D 0x0A (int, Little Endian)
flag = com_writeline("spd", (float)1.234)     // write 0xB6 0xF3 0x9D 0x3F 0x0D 0x0A (float, Little Endian)
flag = com_writeline("spd", (double)123.456)
    // write 0x77 0xBE 0x9F 0x1A 0x2F 0xDD 0x5E 0x40 0x0D 0x0A (double, Little Endian)
flag = com_write("spd", "Hello, World"+newline)
    // write 0x48 0x65 0x6C 0x6C 0x6F 0x2C 0x20 0x57 0x6F 0x72 0x6C 0x64 0x0D 0x0A (string, UTF8)
flag = com_writeline("spd", "Hello, World")
    // write 0x48 0x65 0x6C 0x6C 0x6F 0x2C 0x20 0x57 0x6F 0x72 0x6C 0x64 0x0D 0x0A (string, UTF8)
flag = com_writeline("spd", 1000, 1, 2)  // Invalid in the value, the starting index, and the length
    // write 0xE8 0x03 0x00 0x00 0x0D 0x0A (int, Little Endian)

byte[] bb = {100, 200}
flag = com_writeline("spd", bb)           // write 0x64 0xC8 0x0D 0x0A
flag = com_writeline("spd", bb, 1, 1)     // write 0xC8 0x0D 0x0A
                                          // Array. Retrieve 1 element from the index 1. [1]=200
flag = com_writeline("spd", bb, -1, 1)    // write 0x64 0x0D 0x0A
                                          // Array. Retrieve 1 element from the index 0. [0]=100
flag = com_writeline("spd", "達明機器人", 2)
    // String. Retrieve from the index 2 until the index ends. "機器人"
    // write 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA 0x0D 0x0A (string, UTF8)
string[] ss = {"TM", "", "達明機器人" }
flag = com_writeline("spd", ss)
  // write 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
  0x0D 0x0A
flag = com_write("spd", Byte_Concat(GetBytes(ss), GetBytes(newline)))
  // write 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
  0x0D 0x0A
flag = com_writeline("spd", ss)
  // write 0x54 0x4D 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA
  0x0D 0x0A
flag = com_writeline("spd", ss, 2, 100)
    // Array. Retrieve 100 elements (to the end) from the index 2. [2]=達明機器人
    // write 0xE9 0x81 0x94 0xE6 0x98 0x8E 0xE6 0xA9 0x9F 0xE5 0x99 0xA8 0xE4 0xBA 0xBA 0x0D
    0x0A
```

9. Socket Functions
9.1 Socket Class

Use Socket class and declare variables to create a TCP/IP communication device. The variable name will be the device name.

Construct

Socket *VariableName* = string, int, int

Socket *VariableName* = string, int

Parameter

string	the IP address of the remote host	
int	the connection port of the remote host	
int	read/write timeout in millisecond	0 .. 10000 (10000ms by default)

Note

```
Socket ntd_d1 = "192.168.1.10", 12345
  // construct a device, with IP 192.168.1.10, Port 12345, Timeout 10000ms

Socket ntd_d2 = "192.168.1.11", 9999, 8000
  // construct a device, with IP 192.168.1.10, Port 9999, Timeout 8000ms
```

- In a flow project, it will create a device from the network device list and open it.
- In a script project, after creating a device by the syntax content, it will not connect to the device. It takes the open device function to connect.
- While reading or writing with the device, it confirms if it needs to connect to the device.

9.2 socket_open()

Open a TCP/IP device.

Syntax 1

bool **socket_open**(
    string
)

Parameter

string	TCP/IP device name	

Return

bool	True	Open successfully.
	False	Open unsuccessfully.

Note

Socket ntd_dev = "192.168.1.10", 12345
socket_open("ntd_dev")

9.3 socket_close()

Close a TCP/IP device.

Syntax 1

bool **socket_close**(
    string
)

Parameter

string	TCP/IP device name	

Return

bool	True	Open successfully.
	False	Open unsuccessfully.

Note

```
Socket ntd_dev = "192.168.1.10", 12345
socket_open("ntd_dev")
socket_close("ntd_dev")
```

When a flow project starts running as the Start node initiates, it launches the TCP/IP Socket Client to connect to the specified IP and port. However, as to the script project, users have to use the socket_open function to open and connect to the assigned device.

After connecting to the TCP/IP device, the system keeps receiving the data in the connection, brings the received data to the Received Buffer, and uses respective functions such as Socket_read to read the data. When the project stops running, the existing TCP/IP Socket connection will be closed with the Received Buffer cleared.

The Received Buffer comes with a capacity limit. If the buffer capacity is insufficient when the data comes in, it automatically deletes the oldest data and adds the latest.

9.4 socket_read()

Read data in the Received Buffer and return in a byte array.

Syntax 1

byte[] **socket_read**(
    string
)

Parameters

string	Network device name

Return

byte[]	Return all data in the Received Buffer. Return byte[0] if buffer empty.

Note

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
byte[] var_value = socket_read("ntd_a")
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // ReceivedBuffer = {}
```

*This function reads all data in the Received Buffer and clear the buffer.

Syntax 2

byte[] **socket_read**(
    string,
    int,
    int
)

Parameters

string	Network device name	
int	Retrieve the fixed amount of byte (by the length of byte[])	
	<= 0	Get all
	> 0	Get a specified amount (the specified amount required to get the data)
int	Read time (millisecond)	
	<= 0	Read once
	> 0	Read multiple times until there is data or the times fulfill.

Return

byte[]	Return the specified amount of data in the Received Buffer with a byte array. Return byte[0] if insufficient amount.

Syntax 3

byte[] **socket_read**(
string,
int
)

Note

Same as syntax 2. Fill 0 as the read time by default.

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}

```
byte[] var_value = socket_read("ntd_a", 6)
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C}
  // ReceivedBuffer = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
var_value = socket_read("ntd_a", 100)
  // byte[] = {}          // The number is insufficient for less than 100 bytes in the Received Buffer. Byte[0] will return.
  // ReceivedBuffer = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
var_value = socket_read("ntd_a", 0)
  // byte[] = {0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}          // Retrieve all data
  // ReceivedBuffer = {}
var_value = socket_read("ntd_a", 4, 100)
  // byte[] = {}    // The number is insufficient for less than 4 bytes in the Received Buffer. Byte[0] will return.
                    //But the read time is set to 100 ms, it stays in the function still waiting for data or the read
                    times fulfilled before exiting.
  // ReceivedBuffer = {0x31,0x32,0x33,0x34,0x35,0x36,0x37,0x38}
  // Supposed data received in 50 ms  later
  // byte[] = {0x31,0x32,0x33,0x34}                                  // Retrieve 4 bytes and exit the function.
  // ReceivedBuffer = {0x35,0x36,0x37,0x38}
```

Syntax 4

byte[] **socket_read**(
string,
byte[] or string,
byte[] or string,
int,
int
)

Parameters

string Network device name

byte[] or string
The prefix condition to read. Input byte[0] or "" as the empty string to denote no prefix condition.

byte[] or string
The suffix condition to read. Input byte[0] or "" as the empty string to denote no suffix condition.

int Fetch option

0 The 1st match not required in the beginning and not removing the prefix and the suffix (default)

	1	The 1st match not required in the beginning and removing the prefix and the suffix
	2	The 1st match required in the beginning and removing the prefix and the suffix
	3	The 1st match required in the beginning and removing the prefix and the suffix
int	Read time (millisecond)	
	<= 0	Read once
	> 0	Read multiple times until there is data or the times fulfill.

Return

byte[] Return the 1st array in byte that matches the prefix condition and the suffix condition.

Fetch the first data that matches the conditions in the Received Buffer.only. The following data remains in the Received Buffer.
If the prefix condition and the suffix condition are byte[0] or an empty string, it fetches all data in the Received Buffer.
If unable to find the data matches the condition, it returns byte[0].

Syntax 5

```
byte[] socket_read(
    string,
    byte[] or string,
    byte[] or string,
    int
)
```

Note

Same as syntax 4. Fill 0 as the read time by default.

Syntax 6

```
byte[] socket_read(
    string,
    byte[] or string,
    byte[] or string
)
```

Note

Same as syntax 4. Fill 0 as the fetch option and the read time by default.

```
ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_value = socket_read("ntd_a", "", "")          // No prefix. No suffix. Fetch all data.
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // ReceivedBuffer = {}

ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_value = socket_read("ntd_a", "He", newline)   // Prefix "He" Suffix \u0D0A
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}      // Hello,\u0D0A
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
```

```
  // Fetch the 1st match. Remain the following data.
var_value = socket_read("ntd_a", "", newline, 1)        // Prefix "" Suffix \u0D0A Remove the
  prefix and the suffix.
  // byte[] = {0x57,0x6F,0x72,0x6C,0x64}                  // World
  // ReceivedBuffer = {}
var_value = socket_read("ntd_a", "", newline, 1, 100)
  // Prefix "" Suffix \u0D0A Remove the prefix and the suffix. 100ms
  // byte[] = {}
  // Read byte[0] for fetch option unfulfilled. Wait for 100ms.
  // ReceivedBuffer = {}
  // ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // Supposed data received in 50ms later
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C}                  // Hello,
  // ReceivedBuffer = {}

ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_value = socket_read("ntd_a", "lo", newline)// Prefix "lo" Suffix \u0D0A
  // byte[] = {0x6C,0x6F,0x2C,0x0D,0x0A}                  // lo,\u0D0A
  // The data before the 1st match, {0x48,0x65,0x6C}, will be removed.
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_bb = {}
var_value = socket_read("ntd_a", var_bb, newline)     // Prefix byte[0] Suffix \u0D0A
  // byte[] = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}        // World\u0D0A
  // ReceivedBuffer = {}
var_value = socket_read("ntd_a", var_bb, newline, 0, 100)
  // Prefix byte[0] Suffix \u0D0A，100ms
  // byte[] = {}                          //Read byte[0] for fetch option unfulfilled. Wait for 100ms.
  // ReceivedBuffer = {}
  // ReceivedBuffer = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // Supposed data received in 50ms later
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}
  // ReceivedBuffer = {}

ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,      // $Hello
                  0x23,0x48,0x69,0x0D,0x0A,                     // #Hi
                  0x24,0x54,0x4D,0x0D,0x0A,                     // $TM
                  0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}      // #Robot
byte[] var_value = socket_read("ntd_a", "#", newline, 2)        // Prefix "#" Suffix \u0D0A
  // byte[] = {}
  //Return an empty string for # not in the prefix.
  // ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,0x23,0x48,0x69,0x0D,0x0A,
                       0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", "$", newline, 2)             // Prefix "$" Suffix \u0D0A
  // byte[] = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A}       // Fetch the 1st match in the prefix
  required.
  // ReceivedBuffer = {0x23,0x48,0x69,0x0D,0x0A,
                       0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
```

```
var_value = socket_read("ntd_a", "#", newline, 2)          // Prefix "#" Suffix \u0D0A
  // byte[] = {0x23,0x48,0x69,0x0D,0x0A}                   // Fetch the 1st match in the prefix required.
  // ReceivedBuffer = {0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", "$", newline, 3)          // Prefix "$" Suffix \u0D0A
  // byte[] = {0x54,0x4D}
  // ReceivedBuffer = {0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", "#", newline, 3)          // Prefix "#" Suffix \u0D0A
  // byte[] = {0x52,0x6F,0x62,0x6F,0x74}
  // ReceivedBuffer = {}
```

Syntax 7

byte[] **socket_read**(
string,
byte[] or string,
int,
int
)

Parameters

string Network device name

byte[] or string
The suffix condition to read. Input byte[0] or "" as the empty string to denote no suffix condition.

int Fetch option

0 The 1st match not required in the beginning and not removing the prefix and the suffix (default)

1 The 1st match not required in the beginning and removing the prefix and the suffix

2 The 1st match required in the beginning and removing the prefix and the suffix

3 The 1st match required in the beginning and removing the prefix and the suffix

int Read time (millisecond)

<= 0 Read once

> 0 Read multiple times until there is data or the times fulfill.

Return

byte[] Return the 1st array in byte that matches the suffix condition. (No prefix condition restricted)
Fetch the first data that matches the condition in the Received Buffer.only. The following data remains in the Received Buffer.
If the suffix condition is byte[0] or an empty string, it fetches all data in the Received Buffer.
If unable to find the data matches the condition, it returns byte[0].

Syntax 8

byte[] **socket_read**(
string,
byte[] or string,
int

)

Note

Same as syntax 7. Fill 0 as the read time by default.

Syntax 9

byte[] **socket_read**(
string,
byte[] or string
)

Note

Same as syntax 7. Fill 0 as the fetch option and the read time by default.

```
ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_value = socket_read("ntd_a", "")                    // Empty Suffix. Fetch all data.
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  // ReceivedBuffer = {}

ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
byte[] var_value = socket_read("ntd_a", newline)// Suffix \u0D0A
  // byte[] = {0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A}        // Hello,\u0D0A
  // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}   // Fetch the 1st match. Remain the
  following data.
var_value = socket_read("ntd_a", newline)                      // Suffix \u0D0A
  // byte[] = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}            // World\u0D0A
  // ReceivedBuffer = {}

ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,     // $Hello
                  0x23,0x48,0x69,0x0D,0x0A,                    // #Hi
                  0x24,0x54,0x4D,0x0D,0x0A,                    // $TM
                  0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}     // #Robot
byte[] var_value = socket_read("ntd_a", newline, 0)            // Suffix \u0D0A
  // byte[] = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A}       // $Hello\u0D0A
  // ReceivedBuffer =
  {0x23,0x48,0x69,0x0D,0x0A,0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", newline, 1)                   // Suffix \u0D0A
  // byte[] = {0x23,0x48,0x69}                                 // #Hi
  // ReceivedBuffer = {0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", newline, 2)                   // Suffix \u0D0A
  // byte[] = {0x24,0x54,0x4D,0x0D,0x0A}                       // $TM\u0D0A
  // ReceivedBuffer = {0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
var_value = socket_read("ntd_a", newline, 3)                   // Suffix \u0D0A
  // byte[] = {0x23,0x52,0x6F,0x62,0x6F,0x74}                  // #Robot
  // ReceivedBuffer = {}
```

9.5 socket_read_string()

Read data in the Received Buffer and convert the byte array to string text in UTF8

Syntax 1

string **socket_read_string**(
    string
)

Parameters

string	Network device name

Return

string	Return all data in the Received Buffer. Return an empty string if buffer empty.

Syntax 2

string **socket_read_string**(
    string,
    int,
    int
)

Parameters

string	Network device name	
int	Retrieve the fixed amount of string (by the length of string)	
	<= 0	Get all
	> 0	Get a specified amount (the specified amount required to get the data)
int	Read time (millisecond)	
	<= 0	Read once
	> 0	Read multiple times until there is data or the times fulfill.

Return

string	Return the specified amount of data in the Received Buffer with a string. Return an empty string if insufficient amount.

Syntax 3

string **socket_read_string**(
    string,
    int
)

Note

Same as syntax 2. Fill 0 as the read time by default.

Syntax 4

string **socket_read_string**(
    string,
    byte[] or string,
    byte[] or string,
    int,
    int
)

Parameters

string	Network device name

byte[] or string
The prefix condition to read. Input byte[0] or "" as the empty string to denote no prefix condition.
byte[] or string
The suffix condition to read. Input byte[0] or "" as the empty string to denote no suffix condition.
int Retrieve the fixed amount of string (by the length of string)
<= 0 Get all
> 0 Get a specified amount (the specified amount required to get the data)
int Read time (millisecond)
<= 0 Read once
> 0 Read multiple times until there is data or the times fulfill.

Return

string Return the 1st string that matches the prefix condition and the suffix condition.
Fetch the first data that matches the conditions in the Received Buffer.only. The following data remains in the Received Buffer.
If the prefix condition and the suffix condition are byte[0] or an empty string, it fetches all data in the Received Buffer.
If unable to find the data matches the condition, it returns an empty string.

Syntax 5

```
string socket_read_string(
    string,
    byte[] or string,
    byte[] or string,
    int
)
```

Note

Same as syntax 4. Fill 0 as the read time by default.

Syntax 6

```
string socket_read_string(
    string,
    byte[] or string,
    byte[] or string
)
```

Note

Same as syntax 4. Fill 0 as the fetch option and the read time by default.

Syntax 7

```
string socket_read_string(
    string,
    byte[] or string,
    int,
    int
)
```

Parameters

string Network device name

byte[] or string
The suffix condition to read. Input byte[0] or "" as the empty string to denote no suffix condition.
int Retrieve the fixed amount of string (by the length of string)
<= 0 Get all
> 0 Get a specified amount (the specified amount required to get the data)
int Read time (millisecond)
<= 0 Read once
> 0 Read multiple times until there is data or the times fulfill.

Return

string Return the 1st string that matches the suffix condition. (No prefix condition restricted)
Fetch the first data that matches the condition in the Received Buffer.only. The following data remains in the Received Buffer.
If the suffix condition is byte[0] or an empty string, it fetches all data in the Received Buffer.
If unable to find the data matches the condition, it returns an empty string.

Syntax 8

```
string socket_read_string(
    string,
    byte[] or string,
    int
)
```

Note

Same as syntax 7. Fill 0 as the read time by default.

Syntax 9

```
string socket_read_string(
    string,
    byte[] or string
)
```

Note

Same as syntax 7. Fill 0 as the fetch option and the read time by default.

```
    ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
    string var_value = socket_read_string("ntd_a")
      // string = "Hello, World\u0D0A"
      // ReceivedBuffer = {}

    ReceivedBuffer =
{0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
    string var_value = socket_read_string("ntd_a", 4)
      // string = "TM 達明"       // {0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E} // Fetch 4 by the string length.
      // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
    var_value = socket_read_string("ntd_a", 5, 100)
      // string = ""
```

```
    // The amount to read data in the Received Buffer is less than 5. (by the string length). Wait for 100 ms.
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA, 0x0D, 0x0A}
    // string = "機器人\u0D0A"
    // ReceivedBuffer = {}

  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  string var_value = socket_read_string("ntd_a", "", "")
    // string = "Hello,\u0D0AWorld\u0D0A"
    // ReceivedBuffer = {}
  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  string value = socket_read_string("ntd_a", "He", newline) // Prefix "He" Suffix \u0D0A
    // string = "Hello,\u0D0A"
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", "", newline, 1)
    // Prefix "" Suffix \u0D0A Remove the prefix and the suffix.
    // string = "World"
    // ReceivedBuffer = {}
  var_value = socket_read_string("ntd_a", "", newline, 1, 100)
    // string = ""
    // Read a empty string for the fetch option unfulfilled. Wait for 100 ms.
    // ReceivedBuffer = {}
    // ReceivedBuffer = {0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,0x0D,0x0A}
    // string = "機器人"

  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  string var_value = socket_read_string("ntd_a", "lo", newline)  // Prefix "lo" Suffix \u0D0A
    // string = "lo,\u0D0A"
    // The data before the 1st match, "Hel", will be removed.
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", newline, 1)       // Suffix \u0D0A
    // string = "World"
    // ReceivedBuffer = {}

  ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,     // $Hello
                    0x23,0x48,0x69,0x0D,0x0A,                    // #Hi
                    0x24,0x54,0x4D,0x0D,0x0A,                    // $TM
                    0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}     // #Robot
  string var_value = socket_read_string("ntd_a", "#", newline, 2)      // Prefix "#" Suffix \u0D0A
    // string = ""                                                     // Return an empty string for # not in the prefix.
    // ReceivedBuffer = {0x24,0x48,0x65,0x6C,0x6C,0x6F,0x0D,0x0A,0x23,0x48,0x69,0x0D,0x0A,
                         0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", "$", newline, 2)       // Prefix "$" Suffix \u0D0A
    // string = "$Hello\u0D0A"
    // Fetch the 1st match in the prefix required.
```

```
    // ReceivedBuffer = {0x23,0x48,0x69,0x0D,0x0A,
                         0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", "#", newline, 2)        // Prefix "#" Suffix \u0D0A
    // string = "#Hi\u0D0A"                                       // Fetch the 1st match in the prefix required.
    // ReceivedBuffer = {0x24,0x54,0x4D,0x0D,0x0A,0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}

  var_value = socket_read_string("ntd_a", "$", newline, 3)  // Prefix "$" Suffix \u0D0A
    // string = "TM"
    // ReceivedBuffer = {0x23,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", "#", newline, 3)  // Prefix "#" Suffix \u0D0A
    // string = "Robot"
    // ReceivedBuffer = {}

  ReceivedBuffer =
{0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x0D,0x0A,0x57,0x6F,0x72,0x6C,0x64}
  string var_value = socket_read_string("ntd_a", newline)   // Suffix \u0D0A
    // string = "Hello,\u0D0A"
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}
  var_value = socket_read_string("ntd_a", newline, 0)        // Suffix \u0D0A
    // string = ""
    // Read a empty string for the fetch option unfulfilled.
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}
  var_value = socket_read_string("ntd_a", newline, 1, 100) // Suffix \u0D0A
    // string = ""
    // Read a empty string for the fetch option unfulfilled. Wait for 100ms.
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64}
    // ReceivedBuffer = {0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A,0x31,0x32,0x33,0x0D,0x0A}
    // Supposed the data comes in and fulfills the fetch option.
    // string = "World"
    // ReceivedBuffer = {0x31,0x32,0x33,0x0D,0x0A}
  var_value = socket_read_string("ntd_a", newline, 2)        // Suffix \u0D0A
    // string = "123\u0D0A"
    // ReceivedBuffer = {}
```

9.6 socket_send()

Send the data value to a remote device.

Syntax 1

int **socket_send**(
string,
?,
int,
int
)

Parameters

string	Network device name	
?	The value to write. Available types: int, float, , bool, string, and array. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.	
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

int	Send result	
	1	Sent successfully.
	0	Unable to send the data value as an empty string or an empty array.
	-1	Socket exception occurred during sending.
	-2	Unable to connect to the remote device.
	-3	The device name does not exist, or IP or port is incorrect.

Syntax 2

int **socket_send**(
string,
?,
int
)

Note

Same as syntax 1. Fill 0 as the length of the value to write by default.

Syntax 3

int **socket_send**(
string,
?
)

Note

Same as syntax 1. Fill 0 as the starting index and the length of the value to write by

default.

```
int var_re = socket_send("ntd_a", 100)                    // send 0x64
var_re = socket_send("ntd_a", 1000)                       // send 0xE8,0x03,0x00,0x00 (int, Little Endian)
var_re = socket_send("ntd_a", (float)1.234)
//send 0xB6,0xF3,0x9D,0x3F (float, Little Endian)
var_re = socket_send("ntd_a", (double)123.456)
  // send 0x77,0xBE,0x9F,0x1A,0x2F,0xDD,0x5E,0x40 (double, Little Endian)
var_re = socket_send("ntd_a", "Hello, World"+newline)
  // send 0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A (string, UTF8)
int[] var_ii = {100, 200, 300, 400}
var_re = socket_send("ntd_a", var_ii)
  // send 0x64,0x00,0x00,0x00,0xC8,0x00,0x00,0x00,0x2C,0x01,0x00,0x00,0x90,0x01,0x00,0x00 (int[],
Little Endian)
string[] var_ss = {"TM", "", "Robot"}
var_re = socket_send("ntd_a", var_ss)
  // send 0x54,0x4D,0x52,0x6F,0x62,0x6F,0x74 (string[], UTF8)
  // var_ss[1] is an empty string. The conversion value is still empty.

var_re = socket_send("ntd_a", 1000, 1, 2)
  // Invalid in the value, the starting index, and the length
  // send 0xE8,0x03,0x00,0x00 (int, Little Endian)
var_re = socket_send("ntd_a", "Hello, World"+newline, 0, 7)
  // send 0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20 (string, UTF8)
byte[] var_bb = {100, 200}
var_re = socket_send("ntd_a", var_bb)          // send 0x64,0xC8
var_re = socket_send("ntd_a", var_bb, 1, 1) // send 0xC8
// Array. Read 1 from address 1, [1]=200
var_re = socket_send("ntd_a", var_bb, -1, 1)       // send 0x64
// Array. Read 1 from address 0. [0]=100
var_re = socket_send("ntd_a", "達明機器人", 2)
// Array. Read from address 2 till the end. "機器人"
  // send 0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA (string, UTF8)
var_ss = {"TM", "", "達明機器人"}
var_re = socket_send("ntd_a", var_ss)
   // send 0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA
re = socket_send("ntd_a", Byte_Concat(GetBytes(var_ss), GetBytes(newline)))
  // send
  0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,0x0D,0
  x0A
var_re = socket_send("ntd_a", var_ss, 2, 100)
  // Array. Read 100 from address 2. (till the end) [2]=達明機器人
  // send 0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA
```

9.7 socket_sendline()

Send the data value and add line break symbols, 0x0D 0x0A, to a remote device.

Syntax 1

int **socket_sendline**(
string,
?,
int,
int
)

Parameters

string	Network device name	
?	The value to write. Available types: int, float, , bool, string, and array. Numeric values will be conversed in Little Endian, and string values will be converse in UTF8.	
int	The starting index of the value to write (eligible for strings and arrays)	
	0 .. length-1	Legitimate value
	< 0	Illegitimate value. The starting index will be set to 0.
	>= length	Illegitimate value. The starting index will be set to 0.
int	The length of the value to write (eligible for strings and arrays)	
	<= 0	Write from the starting index to the end of the data.
	> 0	Write from the staring index for a specified number of the length up to the data ends.

Return

int	Send result	
	1	Sent successfully.
	0	Unable to send the data value as an empty string or an empty array.
	-1	Socket exception occurred during sending.
	-2	Unable to connect to the remote device.
	-3	The device name does not exist, or IP or port is incorrect.

Syntax 2

int **socket_sendline**(
string,
?,
int
)

Note

Same as syntax 1. Fill 0 as the length of the value to write by default.

Syntax 3

int **socket_sendline**(
string,
?
)

Note

Same as syntax 1. Fill 0 as the starting index and the length of the value to write by

default.

```
int var_re = socket_sendline("ntd_a", 200)          // send 0xC8,0x0D,0x0A
var_re = socket_sendline("ntd_a", 2000)             // send 0xD0,0x07,0x00,0x00,0x0D,0x0A (int, Little Endian)
var_re = socket_sendline("ntd_a", (float)0.234)     // send 0xB2,0x9D,0x6F,0x3E,0x0D,0x0A (float, Little Endian)
var_re = socket_sendline("ntd_a", (double)0.234)
  // send 0xC1,0xCA,0xA1,0x45,0xB6,0xF3,0xCD,0x3F,0x0D,0x0A (double, Little Endian)
var_re = socket_sendline("ntd_a", "Hello, World"+newline)
  // send 0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x57,0x6F,0x72,0x6C,0x64,0x0D,0x0A,0x0D,0x0A (string, UTF8)
int[] var_ii = {100, 200, 300}
var_re = socket_sendline("ntd_a", var_ii)
  // send 0x64,0x00,0x00,0x00,0xC8,0x00,0x00,0x00,0x2C,0x01,0x00,0x00,0x0D,0x0A (int[], Little Endian)
string[] var_ss = {"TM", "", "Robot"}
var_re = socket_sendline("ntd_a", var_ss)
  // send 0x54,0x4D,0x52,0x6F,0x62,0x6F,0x74,0x0D,0x0A (string[], UTF8)
  / /var_ss[1] is an empty string. The conversion value is still empty.

var_re = socket_sendline("ntd_a", 1000, 1, 2)
  // Invalid in the value, the starting index, and the length
  // send 0xE8,0x03,0x00,0x00,0x0D,0x0A (int, Little Endian)
var_re = socket_sendline("ntd_a", "Hello, World"+newline, 0, 7)
  // send 0x48,0x65,0x6C,0x6C,0x6F,0x2C,0x20,0x0D,0x0A (string, UTF8)
byte[] var_bb = {123, 234}
var_re = socket_sendline("ntd_a", var_bb)           // send 0x7B,0xEA,0x0D,0x0A
var_re = socket_sendline("ntd_a", var_bb, 1, 1)     // send 0xEA,0x0D,0x0A
//Array. Read 1 from address 1.
var_re = socket_sendline("ntd_a", var_bb, -1, 1)    // send 0x7B,0x0D,0x0A
// Array. Read 1 from address 0.
var_re = socket_sendline("ntd_a", "達明機器人", 2)
  //" Array. Read from address 2 till the end. "機器人"
  // send 0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,0x0D,0x0A (string, UTF8)
var_ss = {"TM", "", "達明機器人"}
var_re = socket_sendline("ntd_a", var_ss)
  // send
  0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,0x0D,
  0x0A
var_re = socket_sendline("ntd_a", Byte_Concat(GetBytes(var_ss), GetBytes(newline)))
  // send
  0x54,0x4D,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,0x0D,0x0A,0x0D,
  0x0A
var_re = socket_sendline("ntd_a", var_ss, 2, -1)
  // Array. Read from address 2 till the end. [2]=達明機器人
  // send
```

0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA,*0x0D,0x0A*

10. Manual Decision Functions

10.1 MDecision Class

Use the MDecision class with variable declaration to allow users to configure M-Decision nodes for conditional judgments or to display pop-up messages.

Construct 1

MDecision *VariableName*

MDecision *VariableName* = string, string

Parameter

string	Headline
string	Text

Note

```
MDecision md1                                   // Headline and text are empty strings.
MDecision md2 = "Test1", "MDecision Test"
// The headline is "Test1", and the text, "MDecision Test".
```

Member Methods

Name	Default	Description
Reset()	-	Reset all MDecision parameters to the default.
Title()	""	The pop-up headline
Description()	""	The pop-up text
Timeout()	-1	Timeout
TimeoutDefaultCase()	0	The default index after the timeout
Case()	-	Add, delete, or modify the conditional judgement
Show()		Check the conditional judgement

Reset()

Reset all MDecision parameters to the default.

Syntax 1

void **Reset**(
)

Parameters

void	No input value

Return

void	No return

10.1.2 Title()

Set the pop-up headline

Syntax 1

void **Title**(
string
)

Parameters

string	The headline

Return

void	No return

10.1.3 Description()

Set the pop-up text

Syntax 1

void **Description**(
string
)

Parameters

string	The text

Return

void	No return

10.1.4 Timeout()

Set the stop condition of timeout.

Syntax 1

void **Timeout**(
int,
int
)

Parameters

int	Timeout in millisecond

< 0 Disable
>= 0 Timeout duration

int The default index after timeout

Return

void No return

Syntax 2

void **Timeout**(
int
)

Note

Same as Syntax 1. For setting the timeout duration.

Syntax 3

void **Timeout**(
)

Parameters

void No input value for cancelling the timeout.

Return

void No return

10.1.5 TimeoutDefaultCase()

Set the default index after the timeout

Syntax 1

void **TimeoutDefaultCase**(
int
)

Parameters

int The default index after the timeout.

Return

void No return

10.1.6 Case()

Add, delete, or modify the conditional judgment. It creates a new index if none exists, updates an existing index, or deletes an index if only the index parameter is available.

Syntax 1

void **Case**(
int,
string,
string,
string,
bool
)

Parameters

int The condition or the index of the button in the pop-up
< 0 Error

	>= 0	Legal index value
string	Text to display of the button	
string	Text color of the button	
	"Red"	Set the text color to red.
	"Green"	Set the text color to green.
	"Blue"	Set the text color to blue.
	"Yellow"	Set the text color to yellow.
	"Black"	Set the text color to black.
	"White"	Set the text color to white.
	"Gray"	Set the text color to gray.
string	Background color of the button	
	"Red"	Set the background color to red.
	"Green"	Set the background color to green.
	"Blue"	Set the background color to blue.
	"Yellow"	Set the background color to yellow.
	"Black"	Set the background color to black.
	"White"	Set the background color to white.
	"Gray"	Set the background color to gray.
bool	The conditional can be true/false or a bool return of the statement.	

Return

void	No return

Syntax 2

```
void Case(
    int,
    string,
    string,
    string
)
```

Parameters

int	The condition or the index of the button in the pop-up
string	Text to display of the button
string	Text color of the button
string	Background color of the button

Note

Same as syntax 1. The condition is set to false meaning the condition of the index does not meet.

Syntax 3

```
void Case(
    int,
    string
)
```

Parameters

int	The condition or the index of the button in the pop-up
string	Text to display of the button

Note

Same as syntax 1. The condition is set to false, with the default text color as white and the

default background color as blue.

Syntax 4

void **Case**(
int,
string,
bool
)

Parameters

int	The condition or the index of the button in the pop-up
string	Text to display of the button
bool	The conditional can be true/false or a bool return of the statement.

Note

Same as syntax 1 with the default text color as white and the default background color as blue.

Syntax 5

void **Case**(
int
)

Parameters

int	The condition or the index of the button in the pop-up	
	< 0	Error
	>= 0	Legal index value

Note

Delete the set conditional judgment.

10.1.7 Show()

Check the condition. If it is true, it returns the index value without prompting a pop-up window. If the condition is false, it prompts a pop-up window and continues to loop it concurrently. It returns the respective index value if the condition meets, or the button index value when a user clicks it. If there is a set timeout, it returns the default index value after the timeout.

Syntax 1

int **Show**(
)

Parameters

void	No input value

Return

int	The index value to return

Note

```
int var_count = 0
MDecision md1 = "TM", "Techman Robot?"
md1.Case(1, "Yes")                    // Add index 1, button text "Yes"
md1.Case(2, "OK")                     // Add index 2
md1.Case(3, "No")                     // Add index 3
md1.Case(4, "If", var_count > 100)
// Add index 4, button text "If", and a condition of var_count > 100 for judgment.
```

```
md1.Timeout(10000)                  // Timeout for 10000ms
md1.TimeoutDefaultCase(2)
md1.Case(2)                         // Delete index 2
int re = md1.Show()                 // Return the index that meets the condition or the index where the
                                    button was clicked. If there is a timeout, it returns index 2.
Display(re)

MDecision md2 = "TM", "Techman Robot?"
md2.Case(6, "YES")                  // Add index 6, button text "YES"
md2.Case(2, "OK")                   // Add index 2
md2.Case(1, "NO")                   // Add index 1
md2.Case(2, "OK-2")                 // Modify index 2
int re2 = md2.Show()
Display(re2)
```

11. Parameterized objects

Using parameterized objects is the same as using user defined variables. Parameterized objects can be used without declarations to get or modify point data through the syntaxes in the project operations and make the robot go with more flexibility. The expression comes with 3 parts, item, index, and attribute, and the syntax is shown as below.

```
parameterized item[index].attribute
```

The supported parameterized items include:

1. Point
2. Base
3. TCP
4. VPoint
5. IO
6. Robot
7. FT

Definitions of the indexes and the attributes vary from parameterized items.

Take the reading and writing of the coordinate (attribute) of the Point (item) "P1" (index) as a example. The index is defined as the name of the point, and the attribute, as the data type of float (the same usage as the array's) with modes of reading and writing.

Value	float[]	R/W	point coordinate{X,Y,Z,RX,RY,RZ}

Read values

```
float[] f = Point["P1"].Value          // In the item Point, the index is defined as the name of the point and the data type of string.
float f1 = Point["P1"].Value[0]        // The x value of "P1" can be obtained solely
```

Write values

```
Point["P1"].Value = {0, 0, 90, 0, 90, 0}   // Replace to the coordinate of "P1" with {0,0,90,0,90,0}
Point["P1"].Value[2] = 120                 // or replace the z value of "P1" with 12 solely
```

11.1 Point

Syntax

Base

Point[string].attribute

Item

Point

Index

string The name of the point in the point manager

Attribute

Name	Type	Mode	Description	Format
Value	float[]	R/W	The coordinate of the point	{X, Y, Z, RX, RY, RZ}, Size = 6
Joint	float[]	R/W	The joint angle	{J1, J2, J3, J4, J5, J6}, Size = 6
Pose	int[]	R/W	The pose of the robot	{Config1, Config2, Config3}, Size = 3
Flange	float[]	R	The coordinate of the flange's center	{X, Y, Z, RX, RY, RZ}, Size = 6
BaseName	string	R	The name of the base	"Base Name"
TCPName	string	R	The name of the TCP	"TCP Name"
TeachValue	float[]	R	The original coordinate of the teaching point	{X, Y, Z, RX, RY, RZ}, Size = 6
TeachJoint	float[]	R	The joint angle (the original angle at the teach point)	{J1, J2, J3, J4, J5, J6}, Size = 6
TeachPose	int[]	R	The original pose of the robot on the teaching point	{Config1, Config2, Config3}, Size = 3

*It recalcutes the the Joint and Flange when setting the Value, and it recalcutates the Value and Flange when setting the Joint. Therefore, it reports an error if it cannot calculate the set value.

Note

```
// Read values
float[] f = Point["P1"].Value          / Obtain the coordinate {X, Y, Z, RX, RY, RZ} of "P1"
float f1 = Point["P1"].Value[0]        // or retrieve the x value of "P1" solely
float f1 = Point["P1"].Value[6]        // Return error, exceeding the array's access range
string s =Point["P1"].BaseName         // s ="RobotBase"
// Write values
Point["P1"].Value = {0, 0, 90, 0, 90, 0}   // Replace the coordinate of "P1" with {0,0,90,0,90,0}
Point["P1"].Value[2] = 120                 // or replace the z value of "P1" with 120 solely
Point["P1"].Flange = {0, 0, 90, 0, 90, 0}  // Read only, invalid operation
Point["P1"].Value = {0, 0, 90, 0, 90}  // Return error, writing elements to the array do not match to 6
                                       (writing 5 elements)
Point["P1"].Pose = {1, 2, 4, 0}        // Return error, writing elements to the array do not match to 3
                                       (writing 4 elements)
```

11.2 Base

Syntax

Base

Base[string].attribute or
Base[string, int].attribute

Item

Base

Index

string The name of the base in the base manager
*The name of the base comes with the attribute of the mode in reading without writing only.
"RobotBase"

int The index of the base, available to assign with multiple bases built by vision one shot get all, ranging from 0 as the default to N.

Attribute

Name	Type	Mode	Description	Format
Value	float[]	R/W	The base value	{X, Y, Z, RX, RY, RZ}, Size = 6
Type	string	R	The type of the base	"R": Robot Base "V": Vision Base "C": Custom Base
TeachValue	float[]	R	The original teach base value	{X, Y, Z, RX, RY, RZ}, Size = 6

Note

```
// Read values
float[] f = Base["RobotBase"].Value          // Obtain the base value {0,0,0,0,0,0} of the base "RobotBase"
float f1 = Base["base1"].Value[0]            // or retrieve the x value of "base1" solely
string s =Base["base1"].Type                 // s ="C"
s =Base[Point["P1"].BaseName].Type           // s ="R"    // Given the type of "P1" is "RobotBase"
float[] f = Base["vision_osga",1].Value      // Obtain the 2nd value of the "vision_osga"
// Write values
Base["RobotBase"].Value = {0, 0, 90, 0, 90, 0}      // Read only, invalid operation, because "RobotBase" is the system base
Base["base1"].Value = {0, 90, 0, 0, 90, 0}   // Replace the value of "base1" with {0,90,0,0,90,0}
Base["base1"].Value[4] = 120                 // or replace the RY value of "base1" with 120 solely
Base["base1"].Value[6] = 120                 // Return error, exceeding the array's access range
Base["base1"].Type = "C"                     // Read only, invalid operation
Base["base1"].Value = {0, 0, 90, 0, 90}          // Return error, writing elements to the array do not match to 6 (writing 5 elements)
Base["base1"].Value = {0, 0, 90, 0, 90, 0, 100}  // Return error, writing elements to the array do not match to 6 (writing 7 elements)
```

11.3 TCP

Syntax

TCP

TCP[string].attribute

Item

TCP

Index

string The name of the TCP in the TCP list
*The name of the TCP comes with the attribute of the mode in reading without writing only.
"RobotEndFlange"
"HandCamera"
"HandCamera2"

Attribute

Name	Type	Mode	Description	Format
Value	float[]	R/W	The value of the TCP	{X, Y, Z, RX, RY, RZ}, Size = 6
Mass	float	R/W	The value of mass	Mass in kg
MOI	float[]	R/W	The value of the Principal Moments of Inertia	{Ixx, Iyy, Izz}, Size = 3
MCF	float[]	R/W	The value of Mass center frame with principle axes w.r.t tool frame	{X, Y, Z, RX, RY, RZ}, Size = 6
TeachValue	float[]	R	The original value of the TCP	{X, Y, Z, RX, RY, RZ}, Size = 6
TeachMass	float	R	The original value of mass	Mass in kg
TeachMOI	float[]	R	The original value of the Principal Moments of Inertia	{Ixx, Iyy, Izz}, Size = 3
TeachMCF	float[]	R	The original value of Mass center frame with principle axes w.r.t tool frame	{X, Y, Z, RX, RY, RZ}, Size = 6

Note

```
// Read values
float[] f = TCP["RobotEndFlange "].Value
                                    // Obtain the value {0,0,0,0,0,0} of the TCP " RobotEndFlange "
float f1 = TCP["RobotEndFlange "].Value[0]
                                    // or retrieve the x value of " RobotEndFlange " solely
float mass = TCP["T1"].Mass         // mass = 2.0
float[] moi = TCP["T1"].MOI         // moi = {0,0,0}
float[] mcf = TCP["T1"].MCF         // mcf = {0,0,0,0,0,0}
// Write values
TCP["RobotEndFlange "].Value = {0, -10, 0, 0, 0, 0}
                    // Read only, invalid operation, because " RobotEndFlange " is the system TCP
TCP["T1"].Value = {0, -10, 0, 0, 0, 0}   // Replace the value of "T1"with {0,-10,0,0,0,0}
TCP["T1"].Value[0] = 10             // or replace the X value of "T1" with 10 solely
TCP["T1"].Mass = 2.4                // Replace the mass value of "T1" with 2.4 kg
TCP["T1"].MOI = {0, 0, 0, 1, 2}     // Return error, writing elements to the array do not match
                                    to 3 (writing 5 elements)
```

```
TCP["T1"].MCF = {0, -20, 0, 0, 0, 0, 0}    // Return error, writing elements to the array do not match to 6 (writing 7 elements)
```

11.4 VPoint

Syntax

VPoint

VPoint[string].attribute

Item

VPoint Initial position of the vision job

Index

string The name of the VPoint

Attribute

Name	Type	Mode	Description	Format
Value	float[]	R/W	The initial coordinate of VPoint	{X, Y, Z, RX, RY, RZ}, Size = 6
BaseName	string	R	The name of the VPoint	"Base Name"
TeachValue	float[]	R	The original job initial coordinate of VPoint	{X, Y, Z, RX, RY, RZ}, Size = 6

Note

```
// Read values
float[] f = VPoint["Job1"].Value          // Obtain the initial coordinate {X, Y, Z, RX, RY, RZ} of VPoint "Job1"
float f1 = VPoint["Job1"].Value[0]        // or retrieve the x value of "Job1"
float f1 = VPoint["Job1"].Value[6]        // Return error, exceeding the array's access range
string s = VPoint["Job1"].BaseName// s ="RobotBase"
// Write values
VPoint["Job1"].Value = {0, 0, 90, 0, 90, 0}     // Replace the initial coordinate of VPoint "Job1" with {0,0,90,0,90,0}
VPoint["Job1"].Value[2] = 120             // or replace the Z value of "Job1" with 120 solely
VPoint["Job1"].BaseName = "base1"         // Read only, invalid operation
VPoint["Job1"].Value = {0, 0, 90, 0, 90}        // Return error, writing elements to the array do not match to 6 (writing 5 elements)
VPoint["Job1"].Value = {0, 0, 90, 0, 90, 0, 100}  // Return error, writing elements to the array do not match to 6 (writing 7 elements)
```

11.5 IO

Syntax

IO

IO[string].attribute

Item

IO Input/Output

Index

string The name of the control module

- ControlBox the control box
- EndModule the end module
- ExtModuleN the external module (N = 0 .. n)
- Safety the safety module

Attribute

ControlBox / EndModule / ExtModuleN

Name	Type	Mode	Description	Format
DI	byte[]	R	Digital input	[0] = DI0 0: Low, 1: High [1] = DI1 [n] = DIn
DO	byte[]	R/W	Digital output	[0] = DO0 0: Low, 1: High [1] = DO1 [n] = DOn
AI	float[]	R	Analog input	[0] = AI0 -10.24V .. +10.24V (Voltage) [1] = AI1 [n] = AIn
AO	float[]	R/W	Analog output	[0] = AO0 -10.00V .. + 10.00V (Voltage) [1] = AO1 [n] = AOn
InstantDI	byte[]	R	Digital input (Instant Command)	[0] = DI0 0: Low, 1: High [1] = DI1 [n] = DIn
InstantDO	byte[]	R/W	Digital output (Instant Command)	[0] = DO0 0: Low, 1: High [1] = DO1 [n] = DOn
InstantAI	float[]	R	Analog input (Instant Command)	[0] = AI0 -10.24V .. +10.24V (Voltage) [1] = AI1 [n] = AIn
InstantAO	float[]	R/W	Analog output (Instant Command)	[0] = AO0 -10.00V .. + 10.00V (Voltage) [1] = AO1 [n] = AOn

* The sets of DI[n]/DO[n]/AI[n]/AO[n] vary from the actual hardware device identification.

Safety

Name	Type	Mode	Description	Format
SI	byte[]	R	Safety function input	0: Low, 1: High SI[0] = SF1 User Connected ESTOP input

Name	Type	Mode	Description	Format
				SI[1] = SF3 User Connected External Safeguard Input SI[2] According to Safety Input Ports Assign SI[3] According to Safety Input Ports Assign .. SI[7] According to Safety Input Ports Assign
SO	byte[]	R	Safety function output	0: Low, 1: High SO[0] According to Safety Output Ports Assign SO[1] According to Safety Output Ports Assign SO[2] According to Safety Output Ports Assign SO[3] According to Safety Output Ports Assign .. SO[7] According to Safety Output Ports Assign

The differences between DI/DO/AI/AO and InstantDI/InstantDO/InstantAI/InstantAO

DI/DO/AI/AO is the queue command with reservations in the main flow of the project. If a DI/DO/AI/AO is after the robot motion function such as a point node with the mixture of trajectories, the DI/DO/AI/AO will be operated after the point node is finished. If using an InstantDI/InstantDO/InstantAI/InstantAO command, It will be operated while the point node is on the run and without waiting for the point node to finish.

In addition, if DI/DO/AI/AO turns to an instant command automatically in the thread page of a project as going without waiting for the point node to finish before running along, the result is the same as using InstantDI/InstantDO/InstantAI/InstantAO.

Note

```
// Read values
byte[] di = IO["ControlBox"].DI          // Obtain the digital input status of ControlBox
int dilen = Length(di)                   // Obtain the amount of digital PINs with the size of the array
byte di0 = IO["ControlBox"].DI[0]        // Obtain the status of ControlBox DI[0]
byte di32 = IO["ControlBox"].DI[32]// Return error, exceeding the array's access range (given DI is
                                         an array with the length of 16 where the indexes start with 0
                                         and end with 15.
float[] ai = IO["ControlBox"].AI         // Obtain the analog input status of ControlBox
float[] ao = IO["ControlBox"].AO         // Obtain the analog output status of ControlBox
byte si0 = IO["Safety"].SI[0]            // Obtain the safety input status of Safety SI[0]
byte so4 = IO["Safety"].SO[4]            // Obtain the safety output status of Safety SO[4]
byte si1 = IO["ControlBox"].SI[1]        // Return error, ControlBox does not support SI attribute.
byte di2 = IO["Safety"].DI[2]            // Return error, Safety does not support DI attribute.
byte di7 = IO["ControlBox"].InstantDI[7]// Obtain the status of ControlBox" DI[7] (instant execution)
// Write values
IO["ControlBox"].DI = {1,1,0,0}          // Read only, invalid operation
IO["ControlBox"].DI[0] = 0               // Read only, invalid operation
IO["ControlBox"].DO[2] = 1               // Set DO 2 to High
IO["ControlBox"].AO[0] = 3.3             // Set AO0 to 3.3V
IO["ControlBox"].DO = {1,1,0,0}          // Return error, elements to write mismatch to array's size
                                         (given DI is an array with the length of 16 which covers 16
                                         elements)
```

```
IO["ControlBox"].InstantDO[0] = 1    // Set DO 0 to High (Instant Execution)
IO["Safety"].SI[0] = 0               // Read only, invalid operation
IO["Safety"].SO[4] = 1               // Read only, invalid operation
IO["ControlBox"].SO[1] = 1       // Return error, ControlBox does not support SO attribute.
IO["Safety"].DO[2] = 1           // Return error, Safety does not support DO attribute.
```

11.6 Robot

Syntax

Robot

Robot[int].attribute

Item

Robot

Index

int The index of the robot fixed at 0

Attribute

Name	Type	Mode	Description	Format
CoordRobot	float[]	R	The TCP coordinate of the robot end point opposite to the RobotBase of the robot	{X, Y, Z, RX, RY, RZ}, Size = 6
CoordBase	float[]	R	The TCP coordinate of the robot end point opposite to the current base of the robot.	{X, Y, Z, RX, RY, RZ}, Size = 6
Joint	float[]	R	The current robot joint angle	{J1, J2, J3, J4, J5, J6}, Size = 6
BaseName	string	R	The name of the current base	"Base Name"
TCPName	string	R	The name of the current TCP	"TCP Name"
Payload	float	R	The current compensatory payload	kg
CameraLight	byte	R/W	The lighting of the robot's camera	0: Low (Off), 1: High (On)
InstantCameraLight	byte	R/W	The lighting of the robot's camera (Instant Command)	0: Low (Off), 1: High (On)
TCPForce3D	float	R	The current TCP force as the composite force of the robot base x, y, and z.	N
TCPSpeed3D	float	R	The current TCP speed as a composite speed of the robot base x, y, and z.	mm/s

Note

```
// Read values
float[] rtool = Robot[0].CoordRobot          // Obtain the current TCP coordinate of the robot end point opposite to the RobotBase of the robot
float[] ftool = Robot[0].CoordBase           // Obtain the current TCP coordinate of the robot end point opposite to the current base of the robot.
float f = Robot[0]. CoordBase[0]             // or retrieve the X value of the current TCP coordinate of the robot end point opposite to the current base of the robot solely.
f = Robot[0]. CoordBase[6]                   // Return error, exceeding the array's access range
float[] joint = Robot[0].Joint               // Obtain the current robot joint angle
float j = Robot[0].Joint[0]                  // or retrieve the current angle of the robot's 1st joint solely
string b = Robot[0].BaseName                 // b = "RobotBase"
string t = Robot[0].TCPName                  // t = "RobotEndFlange"
float load = Robot[0].Payload                // 0
```

```
byte light = Robot[0].CameraLight          // light = 0 (OFF)
float tf3d = Robot[0].TCPForce3D           // tf3d = 1.234
float ts3d = Robot[0].TCPSpeed3D           // ts3d = 1.234

// Write values
Robot[0].CoordRobot = {0, 90, 0, 0, 0, 0}      // Read only, invalid operation
Robot[0].CoordBase = {0, 0, 90, 0, 90, 0}      // Read only, invalid operation
Robot[0].BaseName = "Base1"                // Read only, invalid operation
Robot[0].TCPName = "Tool1"                 // Read only, invalid operation
Robot[0].Payload= 3.4                      // Read only, invalid operation
Robot[0].CameraLight = 1                   // Turn on the lighting of the robot's camera
Robot[0].CameraLight = 0                   // Turn off the lighting of the robot's camera
Robot[0].TCPSpeed3D = 1.234                // Read only, invalid operation
```

11.7 FT

Syntax

FT

FT[string].attribute

Item

FT Force Torque sensor status

Index

string The name of F/T sensor in the F/T sensor list

Attribute

Name	Type	Mode	Description	Format
X	float	R	The force value of the X axis	
Y	float	R	The force value of the y axis	
Z	float	R	The force value of the z axis	
TX	float	R	The torque value of the X axis	
TY	float	R	The torque value of the y axis	
TZ	float	R	The torque value of the z axis	
F3D	float	R	The XYZ resultant force value	
T3D	float	R	The XYZ torque value	
Value	float[]	R	The XYZ resultant force value and torque value array.	{X, Y, Z, TX, TY, TZ}, Size = 6
ForceValue	float[]	R	The XYZ resultant force value array	{X, Y, Z}, Size = 3
TorqueValue	float[]	R	The XYZ torque value array	{TX, TY, TZ}, Size = 3
RefCoordX	float	R	The X-axis force value measured based on the reference base set in the node	
RefCoordY	float	R	The Y-axis force value measured based on the reference base set in the node	
RefCoordZ	float	R	The Z-axis force value measured based on the reference base set in the node	
RefCoordTX	float	R	The X-axis torque value measured based on the reference base set in the node	
RefCoordTY	float	R	The Y-axis torque value measured based on the reference base set in the node	
RefCoordTZ	float	R	The Z-axis torque value measured based on the reference base set in the node	
RefCoordF3D	float	R	The XYZ resultant force value measured based on the reference base set in the node	

Name	Type	Mode	Description	Format
RefCoordT3D	float	R	The XYZ torque measured based on the reference base set in the node	
RefCoordForceValue	float[]	R	The XYZ resultant force value matrix measured based on the reference base set in the node	{RefCoordX, RefCoordY, RefCoordZ}, Size = 3
RefCoordTorqueValue	float[]	R	The XYZ torque value matrix measured based on the reference base set in the node	{RefCoordTX, RefCoordTY, RefCoordTZ}, Size = 3
Model	string	R	The Model name of the F/T sensor	
Zero	byte	R/W	Turn on or off F/T sensor offset	0: Zero OFF, 1: Zero ON

Attributes associated with RefCoord come with values when in Force Control.

Note

```
// Read values
float x = FT["fts1"].X                  // Obtain the current X-axis force value of F/T sensor "fts1"
float tx = FT["fts1"].TX                // Obtain the current X-axis torque value of F/T sensor "fts1"
float f3d = FT["fts1"].F3D              // Obtain the current XYZ resultant force value of F/T sensor "fts1"
float[] force = FT["fts1"].ForceValue   // Obtain the current XYZ resultant force value array of
                                        F/T sensor "fts1"
string mode = FT["fts1"].Model          // Obtain the model name of F/T sensor "fts1"
// Write values
FT["fts1"].Y = 3.14                     // Read only, invalid operation
FT["fts1"].TY = 1.34                    // Read only, invalid operation
FT["fts1"].T3D = 4.13                   // Read only, invalid operation
FT["fts1"].TorqueValue = {1.1, 2.2, 3.3} // Read only, invalid operation
FT["fts1"].Zero = 1                     // Book the current offset of F/T sensor
```

11.8 Env

Syntax

Environment

Env. Attributes

Item

Env Current application environment status

Attributes

Name	Type	R/W	Description	Format
AppVersion	string	R	Application Version	"2.24.1000"
AppType	int	R	Application Type	1: Real Robot 2: Virtual Robot 3: TM AI+ AOI Edge
RobotModel	string	R	Robot Model	"TM12S"、"TM5-900" …
CurrentProject	string	R	Project Name	"ProjectName"
RunningProject	string	R	Current Running Project Name	"ProjectName"
RunningSpeed	float	R	Current Running Speed	Represented in percentage (%)
OperationMode	int	R	Operation Mode	0: Manual 1: Auto

* When using the Warp node or RedirectToProject(), the CurrentProject and the RunningProject may vary.

Note

```
string version = Env.AppVersion      // "2.24.1000"
int type = Env.AppType               // If the application actively connects to a virtual robot, then type is 2

float speed = Env.RunningSpeed       // If the current project speed is 5%, then speed is 5%.
int op = Env.OperationMode           // If the current mode is automatic, then op is 1.
```

12. Robot Teach Class

12.1 *TPoint Class*

Use TPoint Class and declare variables to create the point names and the point values. The variable name will be the point name. *It takes calculations for the values of the coordinates and the angles to construct points. It returns an error if it fails to calculate tthe values of the coordinates and the angles with the parameter values.

Construct 1

TPoint *VariableName* = float[]

TPoint *VariableName* = float, float, float, float, float, float

Parameters

float[] The Robot End TCP Coordinate: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°) recorded by RobotBase and RobotEndFlange TCP.

Note

```
TPoint p1 = {0,-282.75,1094.9,90,0,0}
                    // the coordinate value 0,-282.75,1094.9,90,0,0 by RobotBase and
                    RobotEndFlange
TPoint p2 = 517.5,-147.8,442.45,180,0,90
                    // the coordinate value 517.5,-147.8,442.45,180,0,90 by RobotBase and
                    RobotEndFlange
```

Construct 2

TPoint *VariableName* = string, float[]

TPoint *VariableName* = string, float, float, float, float, float, float

Parameters

string Point Definitions. Default to "C".

- "C" Point coordinate. When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.(Same as Construct 1)
- "D" Point coordinate. When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
- "J" Joint angle. When the project operation ends, it does not the values back to the record file. It uses the declared values with the next project operation.
- "JD" Joint angle. When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.

float[] If expressed in coordinates, this is the six elements of the TCP coordinates at the robot end: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°); if expressed in angles, the six elements of the robot joints: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°) by the RobotBase base and RobotEndFlange TCP records.

Note

```
TPoint p3 = "D",{522.07,130.75,442.45,180,0,120}
TPoint p4 = "D",134.95,-147.8,1094.9,90,0,90    // Return error，unable to calculate the angle value by the coordinate value
TPoint p5 = "J",0,0,90,0,90,0
// the angle value 0,0,90,0,90,0 by RobotBase and RobotEndFlange
TPoint p6 = "JD",{30,0,90,0,90,0}
// the angle value 30,0,90,0,90,0 by RobotBase and RobotEndFlange
```

Construct 3

TPoint *VariableName* = string, float[], string, string

TPoint *VariableName* = string, float, float, float, float, float, float, string, string

TPoint *VariableName* = float[], string, string

TPoint *VariableName* = float, float, float, float, float, float, string, string

Parameters

string	Point Definitions. Default to "C".
"C"	Point coordinate. When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.
"D"	Point coordinate. When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
"J"	Joint angle. When the project operation ends, it does not the values back to the record file. It uses the declared values with the next project operation.
"JD"	Joint angle. When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
float[]	If expressed in coordinates, this is the six elements of the TCP coordinates at the robot end: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°); if expressed in angles, the six elements of the robot joints: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°). Record by the base name and the TCP name.
string	Base name. Use the current base name in the record if an empty string.
string	TCP name. Use the current TCP name in the record if an empty string.

Note

```
TBase base1 = 0,0,90,0,0,0
TTCP tcp1 = 0,0,10,0,0,0
TPoint p7 = "D",{0,-282.75,1094.9,90,0,0},"RobotBase"," RobotEndFlange "
TPoint p8 = "J",0,0,90,0,90,0,"base1"," RobotEndFlange "// by base1 and RobotEndFlange
TPoint p9 = "JD",{30,0,90,0,90,0},"RobotBase","tcp1"    // by RobotBase and tcp1
TPoint p0 = "C",{517.5,-147.8,342.45,180,0,90},"base1","tcp1" // by base1 and tcp1
// The syntax below is in the non-define section.
ChangeBase("base1")
TPoint p00 = {517.5,-147.8,342.45,180,0,90},"","tcp1"    // by the current base1 and the assigned tcp1
```

Construct 4

TPoint *VariableName* = string, float[], float[], string, string
TPoint *VariableName* = string, float[], float[]
TPoint *VariableName* = float[], float[], string, string
TPoint *VariableName* = float[], float[]

Parameters

string	Point Definitions. Default to "C".
"C"	When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.
"D"	When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
float[]	Expressed in coordinates, this is the six elements of the TCP coordinates at the robot end: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°).
float[]	Expressed in angles, the six elements of the robot joints: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°). Record by the base name and the TCP name.
string	Base name. Use the current base name in the record if an empty string.
string	TCP name. Use the current TCP name in the record if an empty string.

Note

```
TBase base1 = 0,0,90,0,0,0
TTCP tcp1 = 0,0,10,0,0,0
TPoint tp1 = "C",{0,-282.75,1094.9,90,0,0},{0,0,0,0,0,0},"RobotBase"," RobotEndFlange
"
TPoint tp2 = "D",{517.5,-147.8,442.45,180,0,90},{0,0,90,0,90,0}
// by RobotBase and RobotEndFlange
TPoint tp3 = {0,-292.75,1004.9,90,0,0},{0,0,0,0,0,0},"base1","tcp1"  // by base1 and tcp1
TPoint tp4 = {134.95,-147.8,1094.9,90,0,90},{0,0,0,0,90,0}
// by RobotBase and RobotEndFlange
// The syntax below is in the non-define section.
ChangeBase("base1")
ChangeTCP("tcp1")
TPoint tp5 = {0,-292.75,1004.9,90,0,0},{0,0,0,0,0,0},"","" // by the current base1 and the
current tcp1
```

Member Attibutes

Name	Type	Mode	Description	Format
Value	float[]	R/W	Point coordinate	{X, Y, Z, RX, RY, RZ}, Size = 6
Joint	float[]	R/W	Joint angle	{J1, J2, J3, J4, J5, J6}, Size = 6
Pose	int[]	R/W	Robot pose	{Config1, Config2, Config3}, Size = 3
Flange	float[]	R	Flange center coordinate	{X, Y, Z, RX, RY, RZ}, Size = 6
BaseName	string	R	Base name	"Base Name"
TCPName	string	R	TCP name	"TCP Name"
TeachValue	float[]	R	Point coordinate (the original teach point coordinate)	{X, Y, Z, RX, RY, RZ}, Size = 6

Name	Type	Mode	Description	Format
TeachJoint	float[]	R	Joint angle (the original teach point angle)	{J1, J2, J3, J4, J5, J6}, Size = 6
TeachPose	int[]	R	Robot pose (the original teach point pose)	{Config1, Config2, Config3}, Size = 3

* It recalculates the Joint and the Flange while setting the Value, and it recalculates the Value and the Flange while setting the Joint. Therefore, it returns an error if failed to calculate.

Note

```
TPoint P1 = {0,-282.75,1094.9,90,0,0}
                    // "P1"Coordinate value 0,-282.75,1094.9,90,0,0 by RobotBase and
                    RobotEndFlange
// Read values
float[] f = P1.Value          // Get the point coordinate of the point "P1" {0,-282.75,1094.9,90,0,0}
float f1 = P1.Value[1]        // or get the Y value along of point "P1"
float f2 = P1.Value[6]        // Return error. Exceeding the array's access range
float[] f3 = P1.Joint         // Get the angle value of the point "P1" {0,0,0,0,0,0}
string s = P1.BaseName        // s = "RobotBase"
// Write values
P1.Value = {517.5,-147.8,442.45,180,0,90}   // Modify the point coordinate of the point "P1" to
                                            {517.5,-147.8,442.45,180,0,90}
P1.Value[2] = 450                           // or modify the z value along of point "P1" to 450
P1.Flange = {0,0,90,0,90,0}                 // Read only, invalid operation
P1.Value = {0,0,90,0,90}      // Return error. The amount of the array elements to wirte does not matach
                              to 6. (5)
P1.Pose = {1,2,4,0}           // Return error. The amount of the array elements to wirte does not matach to 3.
                              (4)
```

12.2 *TBase Class*

Use TBase Class and declare variables to create the point names and the point values. The variable name will be the point name.
*The system base name comes with the attribute of the read-only mode and without the write mode.
"RobotBase"
Once the variable name is the system base name, it is for variable declaration only. The input value is invalid in the construct.

Construct 1

TBase *VariableName* = float[]
TBase *VariableName* = float, float, float, float, float, float

Parameters

float[] Base Value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Note

```
TBase base1 = {0,0,90,0,0,0}        // Name: base1, Type: C, Value: 0,0,90,0,0,0
TBase base2 = 0,90,90,0,0,0         // Name: base2, Type: C, Value: 0,90,90,0,0,0
TBase RobotBase = 0,0,90,0,0,90
                  // Since RobotBase is the system base, the input values are void but variable
                  declarations.
```

Construct 2

TBase *VariableName* = string, float[]
TBase *VariableName* = string, float, float, float, float, float, float

Parameters

string Base Types. Default to "C".
- "C" When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.(Same as Construct 1)
- "D" When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
- "V" Defined the same as type "D." This type goes with vision jobs mainly. The name must comply with the naming rule beginning with *vision_*.
  * Only in the define variable section will the variable declaration come with the write back to the record file mechanism.

float[] Base Value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Note

```
TBase base5 = "C",{0,0,90,0,0,0}              // Name: base5, Type: C, Value: 0,0,90,0,0,0
TBase base6 = "D",0,90,90,0,0,0               // Name: base6, Type: D, Value: 0,90,90,0,0,0
TBase vision_base7 = "V",90,90,90,0,0,0       // Name: vision_base7, Type: V, Value:
                                              90,90,90,0,0,0
TBase base8 = "V",90,90,90,0,0,0
              // Return error. The name, base8 , does not comply the naming rule of the type
              V.
```

Member Attibutes

Name	Type	Mode	Description	Format
Value	float[]	R/W	Base value	{X, Y, Z, RX, RY, RZ}, Size = 6
Type	string	R	Base type	"R": Robot Base "C": Custom Base "D": Custom Base with write-back "V": Vision Base
TeachValue	float[]	R	Base value (the original teach point base value)	{X, Y, Z, RX, RY, RZ}, Size = 6

Member Methods

Name	Description
GetValue()	Retrieve the base value
SetValue()	Set the base value
ConShift()	Convert a new base value (the original teach value) with the base value and the shift value.

12.2.1 GetValue()

Retrieve the base value. (applicable to multiple bases created in the vision jobs)

Syntax 1

float[] **GetValue**(
int
)

Parameters

int	Base Index. Users can assign from multiple bases created by vision one shot get all. The index is 0 to N and defaulted to 0.Base Index. Users can assign from multiple bases created by vision one shot get all. The index is 0 to N and defaulted to 0.

Return

float[]	Base Value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°) If the base index value is larger than the number of multiple bases, it returns an empty array.

12.2.2 SetValue()

Set the base value. (applicable to multiple bases created in the vision jobs)

Syntax 1

bool **SetValue**(
int,
float[]
)

Parameters

int	Base Index. Users can assign from multiple bases created by vision one shot get all. The index is 0 to N and defaulted to 0.
float[]	Base Value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Return

bool Return True if successful. Return False if failed.
If the base index value is larger than the number of multiple bases, it sets failed.

Note

```
TBase base1 = {0,0,90,0,0,0}          // Name: base1, Type: C, Value: 0,0,90,0,0,0
TBase RobotBase = 0,0,90,0,0,90
// Since RobotBase is the system base, the input values are void but variable declarations.
TBase base5 = "C",{0,0,90,0,0,0}              // Name: base5, Type: C, Value: 0,0,90,0,0,0
TBase base6 = "D",0,90,90,0,0,0               // Name: base6, Type: D, Value: 0,90,90,0,0,0
TBase vision_base8 = "V",90,90,90,0,0,0
// Name: vision_base8, Type: V, Value: 90,90,90,0,0,0

// Read values
float[] b1 = base1.Value          // Base: "base1", Value: {0,0,90,0,0,0}
float[] b2 = RobotBase.Value      // Base: "RobotBase", Value {0,0,0,0,0,0}
float b3 = base1.Value[2]         // Z value of Base "base1": 90
string t1 = base5.Type            // "C"
string t2 = base6.Type            // "D"
string t3 = vision_base8.Type     // "V"
float[] b50 = base5.GetValue(0) // {0,0,90,0,0,0} Obtain the 1st base value in the base "base5".
float[] b51 = base5.GetValue(1)       // {} empty array Obtain the 2nd base value in the base "base5".
float[] vb = vision_base8.GetValue(1)     // Obtain the 2nd base value in the base"vision_base8".
                                          // Suppose there is a vision job, it creates and updates the base
                                          value of vision_base8.
// Write values
RobotBase.Value = {0,0,90,0,90,0} // Read only, invalid operation for "RobotBase" being the
                                  system base.
base1.Value = {0,90,0,0,90,0}     // Modify the base "base1" to {0,90,0,0,90,0}
base1.Value[4] = 120              // or modify the the RY value of the base "base1" alone to 120.
base1.Value[6] = 120              // Return error. Exceeding the array's access range.
base1.Type = "C"                  // Read only, invalid operation
base1.Value = {0,0,90,0,90}
// Return error. The amount of the array elements to wirte does not matach to 6. (5)
base1.Value = {0,0,90,0,90,0,100}
// Return error. The amount of the array elements to wirte does not matach to 6. (7)
base6.Value = {30,90,90,0,0,0}    // Write back to the record file since "base6" is type D.
base5.SetValue(0, {90,90,90,0,0,0}) // True. Set the 1st coordinate value in the base "base5".
base5.SetValue(1, {0,0,0,90,90,90}) // False. Failed to set.
```

12.2.3 ConvShift()

Convert a new base value with the base value (the original base teach value) and the shift value, where the shift depends on the position and direction of the original coordinate.

Syntax 1

```
float[] ConvShift(
    float[]
```

)

Parameters

float[] Shift value $X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Return

float[] the new base value calculated by the given position and direction of the original base teach value and the shift value.
$X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Syntax 2

float[] **ConvShift**(
float, float, float, float, float, float
)

Note

Same as Syntax 1. It replaces the float[] type with float,float,float,float,float,float parameters.

Syntax 3

float[] **ConvShift**(
float[],
float[]
)

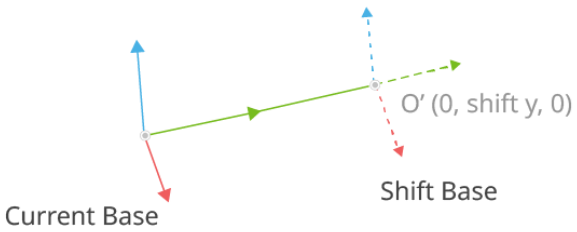
Parameters

float[] Base value $X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$
float[] Shift value $X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Return

float[] the new base value calculated by the given position and direction of the original base teach value and the shift value.
$X_{(mm)}$ $Y_{(mm)}$ $Z_{(mm)}$ $RX_{(°)}$ $RY_{(°)}$ $RZ_{(°)}$

Note




```
TBase base1 = {200,200,0,0,0,90}          // Name: base1, Type: C, Vaule: 200,200,0,0,090

float[] base_shift = {10,20,30,0,0,0}
float[] new_base = {0,0,0,0,0,0}

base1.Value = base1.ConvShift(base_shift)                    // {180,210,30,0,0,90}
new_base = base1.ConvShift(10,20,30,0,0,0)                   // {180,210,30,0,0,90}
new_base = base1.ConvShift(base1.Value, {10,20,30,0,0,0})    // {160,220,60,0,0,90}
new_base = base1.ConvShift(base1.TeachValue, {10,20,30,0,0,0}) // {180,210,30,0,0,90}
```

12.3 *TTCP Class*

Use TTCP Class and declare variables to create the point names and the point values. The variable name will be the point name.
*The system TCP name comes with the attribute of the read-only mode and without the write mode.

"RobotEndFlange"
"HandCamera"
"HandCamera2"

Once the variable name is the system TCP name or is in the tool setting of TMflow, it is for variable declaration only. The input value is invalid in the construct.

Construct 1

TTCP *VariableName* = float[], float
TTCP *VariableName* = float[]
TTCP *VariableName* = float, float, float, float, float, float, float
TTCP *VariableName* = float, float, float, float, float, float

Parameters

float[] TCP value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)
float Tool Mass (kg). Default to 0.

Note

```
TTCP tcp1 = {0,0,90,0,0,0}      // Name: tcp1, Type: C, Value: 0,0,90,0,0,0, Mass: 0 kg
TTCP tcp2 = {0,0,90,0,0,0},2    // Name: tcp2, Type: C, Value: 0,0,90,0,0,0, Mass: 2 kg
TTCP tcp3 = 0,0,90,0,0,0        // Name: tcp3, Type: C, Value: 0,0,90,0,0,0, Mass: 0 kg
TTCP tcp4 = 0,0,90,0,0,0,2      // Name: tcp4, Type: C, Value: 0,0,90,0,0,0, Mass: 2 kg
TTCP RobotEndFlange = 0,0,90,0,0,90
                // Since RobotEndFlange is the system tool name, the input values are void but variable declarations.
```

Construct 2

TTCP *VariableName* = string, float[], float
TTCP *VariableName* = string, float[]
TTCP *VariableName* = string, float, float, float, float, float, float, float
TTCP *VariableName* = string, float, float, float, float, float, float

Parameters

string Tool Types. Default to "C".
- "C" When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.(Same as Construct 1)
- "D" When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.
- "V" Defined the same as type "D." This type goes with vision jobs mainly. The name must comply with the naming rule beginning with *vision_*.
  * Only in the define variable section will the variable declaration come with the write back to the record file mechanism.

float[] TCP value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)
float Tool Mass (kg). Default to 0.

Note

TTCP tcp5 = "C",{0,0,90,0,0,0} // Name: tcp5, Type: C, Value: 0,0,90,0,0,0, Mass: 0 kg

TTCP tcp6 = "D",{0,90,90,0,0,0},2 // Name: tcp6, Type: D, Value: 0,90,90,0,0,0, Mass: 2 kg

TTCP visionTCP_tcp7 = "V",90,90,90,0,0,0 // Name: visionTCP_tcp7, Type: V, Value: 90,90,90,0,0,0

TTCP tcp7v = "V",90,90,90,0,0,0

// Return error. The name, tcp7v, does not comply the naming rule of the type V.

TTCP tcp8 = "D",90,90,90,0,0,0,2 // Name: tcp8, Type: D, Value: 90,90,90,0,0,0, Mass: 2 kg

Construct 3

TTCP *VariableName* = string, float[], float, float[], float[]

TTCP *VariableName* = float[], float, float[], float[]

Parameters

string Tool Types. Default to "C".

"C" When the project operation ends, it does not write the values back to the record file. It uses the declared values with the next project operation.(Same as Construct 1)

"D" When the project operation ends, it writes the values back to the record file. It prioritizes using the record file with the next project operation. If the record file comes empty, it uses the declared values.

"V" Defined the same as type "D." This type goes with vision jobs mainly. The name must comply with the naming rule beginning with *vision_*.

* Only in the define variable section will the variable declaration come with the write back to the record file mechanism.

float[] TCP value: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

float Tool Mass (kg). Default to 0.

float[] Principal Moments of Inertia: Ixx(kg-mm^2), Iyy(kg-mm^2), Izz(kg-mm^2)

float[] Mass Center Frame with Principle Axes w.r.t Tool Frame: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Note

TTCP tcp9 = {0,0,90,0,0,0},2,{2,0.5,0.5},{0,0,-80,0,0,0}

// Name: tcp9, Type: C, Value: 0,0,90,0,0,0, Mass: 2 kg, Inertia: 2,0.5,0.5, The Reference Coordinate: 0,0,-80,0,0,0

TTCP tcp0 = "D",{0,0,150,0,0,90},1,{1,0.5,0.5},{0,0,-80,0,0,0}

// Name: tcp0, Type: D, Value: 0,0,150,0,0,90, Mass: 1 kg, Inertia: 1,0.5,0.5, The Reference Coordinate: 0,0,-80,0,0,0

Member Attibutes

Name	Type	Mode	Description	Format
Value	float[]	R/W	TCP value	{X, Y, Z, RX, RY, RZ}, Size = 6
Mass	float	R/W	Mass	Mass in kg
MOI	float[]	R/W	Principal Moments of Inertia	{Ixx, Iyy, Izz}, Size = 3
MCF	float[]	R/W	Mass center frame with principle axes w.r.t tool frame	{X, Y, Z, RX, RY, RZ}, Size = 6

Name	Type	Mode	Description	Format
TeachValue	float[]	R	TCP value (the original TCP setting value)	{X, Y, Z, RX, RY, RZ}, Size = 6
TeachMass	float	R	Mass (the original TCP setting value)	Mass in kg
TeachMOI	float[]	R	Principal Moments of Inertia (the original TCP setting value)	{Ixx, Iyy, Izz}, Size = 3
TeachMCF	float[]	R	Mass center frame with principle axes w.r.t tool frame (the original TCP setting value)	{X, Y, Z, RX, RY, RZ}, Size = 6

Note

```
TTCP tcp1 = {0,0,90,0,0,0},3          // Name: tcp1, Type: C, Value: 0,0,90,0,0,0, Mass: 3 kg
TTCP RobotEndFlange = 0,0,90,0,0,90
                // Since RobotEndFlange is the system tool name, the input values are void but variable
                declarations.
TTCP tcp9 = "D",{0,0,90,0,0,0},2,{2,0.5,0.5},{0,0,-80,0,0,0}
// Read values
float[] t0 = RobotEndFlange.Value
// Obtain the TCP value of the tool named RobotEndFlange: {0,0,0,0,0,0}
float[] t1 = tcp1.Value          // Obtain the TCP value of the tool named tcp1: {0,0,90,0,0,0}
float t2 = tcp1.Value[2]         // or obtain the Z value of the tool named tcp1 alone.
float mass = tcp1.Mass           // mass = 3
float[] mcf = tcp1.MCF           // mcf = {0,0,0,0,0,0}
float mass9 = tcp9.Mass          // mass9 = 2      // Obtain 2.1 kg if operate after tcp9.Mass = 2.1
float[] moi9 = tcp9.MOI          // moi9 = {2,0.5,0.5}
// Write values
RobotEndFlange.Value = {0, -10, 0, 0, 0, 0}
                        // Read only, invalid operation for RobotEndFlange being the system TCP.
tcp1.Value = {0, -10, 0, 0, 0, 0}  // Modify the TCP named tcp1 to {0,-10,0,0,0,0}
tcp1.Value[0] = 10                 // or modify the X value of tcp1 alone to 10
tcp1.Mass = 2.4                    // Modify the the mass of the TCP named tcp1 to 2.4 kg.
tcp9.Mass = 2.1                    // Modify the the mass of the TCP named tcp9 to 2.1 kg.
tcp1.MOI = {0, 0, 0, 1, 2}         // Return error. The amount of the array elements to wirte does not
                                   matach to 3. (5)
tcp1.MCF = {0, -20, 0, 0, 0, 0, 0}
                                   // Return error. The amount of the array elements to wirte does not
                                   matach to 6. (7)
```

13. Robot Motion & Vision Job Function

For robot motion functions and vision job functions to be available if using flow projects, it requires the External Script to have the project flow enter the Listen node (external script control mode) or the script node. If using script project programming, they are available in the project programming directly.

Calling in the main thread, namely, the main flows or subflows in the flow projects, or the main functions and the functions to call in the script projects, is mandatory for robot motion functions and vision job functions moving to the initial position.Calling motion functions is not allowed in other threads. All the motion processes will be queued temporarily and processed in sequence. Users can use the queue tag numbers to understand the current motion command process if necessary.

13.1 QueueTag()

Set robot motions with Queue Tag Numbers to denote the current robot motion in process. The status of each queue tag can be monitored using TMSTA SubCmd 01.

Syntax 1

bool **QueueTag**(
    int,
    int
)

Parameters

int	The tag number. Valid for integers between 1 and 15.	
int	Wait for the tagging to continue processing or not.	
	0	Not wait (default)
	1	Wait
	When the value is set to 1, the process stays in the function and waits for the tagging to complete and continue processing.	

Return

bool Return True when tagged successfully. Return False when tagged unsuccessfully.

Syntax 2

bool **QueueTag**(
    int
)

Note

Same as syntax 1. It default to 0 not waiting for the tagging to continue processing.

13.2 WaitQueueTag()

Wait for the Queue Tag Number of the robot motion to complete.

Syntax 1

int **WaitQueueTag**(
int,
int
)

Parameters

int The tag number
1..15 Valid tag numbers.
0 Invalid tag number, but waits for the timeout. (No waiting for the time out if set the timeout to infinite.)
<0 Unavailable tag number. No waiting for the time out.
>15 Unavailable tag number. No waiting for the time out.

int Set the time to the timeout
< 0 Wait infinitely. Valid when the tag number is between 1 to 15 legitimately. (default) = 0 Wait to check once
> 0 Wait in milliseconds before timeout
When using waiting in queue, the process stays in the function until the tagging is completed, the tagging is not existed, or timeout, and then continues processing.

Return

int Return the result of waiting
1 The tagging is completed
0 The tagging is incomplete or timeout
-1 The tagging is not existed

* Tag numbers can be reused.
* The tag number will retain the status of the final four tags, and if the tag number did not occur or exceeds them, it returns not existed.

Syntax 2

int **WaitQueueTag**(
int
)

Note

The syntax is the same as syntax 1. The default is no timeout and required to wait for the tagging to complete (or not existed)
WaitQueueTag(int, int) => **WaitQueueTag**(int, 0)

Syntax 3

void **WaitQueueTag**(
)

Parameters

void No input value

Return

void No return

Note

No tag number is required. It waits for all the robot motions in the current queue to complete before going forward execution.

13.3 CheckQueueTag()

Check the Queue Tag Number of the robot motion to complete.

Syntax 1

int **CheckQueueTag**(

int

)

Parameters

int The tag number

1..15 Valid tag numbers.

Return

int Return the result of checking

1 The tagging is completed.

0 The tagging is incomplete.

-1 The tagging is not existed.

* Tag numbers can be reused.

* The tag number will retain the status of the final four tags, and if the tag number did not occur or exceeds them, it returns not existed.

* Same as WaitQueueTag(int, 0) and denotes the result of one time checking only tag number.

Motion Function Queue Tag

Motion function queue tags are used to cooperate with the robot motion functions. Since all motion functions are queued in the buffer and executed in order, use the cooperative queue tags, it is possible to know which motion function is in execution currently.

1. < $***TMSCT***,172,2,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1)\r\n // QueueTag(1) not wait and continue processing
float[] targetP2 = {0,0,90,90,0,0}\r\n
PTP("JPP",targetP2,10,200,10,false)\r\n
QueueTag(2)\r\n // QueueTag(2) not wait and continue processing
,*49\r\n

When executed the script content, since QueueTag() did not wait, after execution, the process returned

> $***TMSCT***,4,2,OK,*5F\r\n

When robot motion executed PTP() targetP1, because of QueueTag(1), it will return

> $***TMSTA***,10,01,01,true,*64\r\n // TMSTA SubCmd 01, TagNumber 01, completed

When robot motion executed PTP() targetP2, because of QueueTag(2) , it will return

> $***TMSTA***,10,01,02,true,*67\r\n // TMSTA SubCmd 01, TagNumber 02, completed

2. < $***TMSCT***,174,2,float[] targetP3= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP3,10,200,0,false)\r\n
QueueTag(3,1)\r\n // QueueTag(3) wait and stay in the function until the tagging completed
float[] targetP4 = {0,0,90,90,0,0}\r\n
PTP("JPP",targetP4,10,200,10,false)\r\n
QueueTag(4)\r\n // QueueTag(4) not wait and continue processing
,*56\r\n

When executed the script content, since QueueTag(3,1) is set to wait, after tagging completed, the process returned

> $***TMSTA***,10,01,03,true,*66\r\n // TMSTA SubCmd 01, TagNumber 03, completed

When QueueTag(3) completed, the process continues, since QueueTag(4) is not set to wait, after execution, the process returned

> $***TMSCT***,4,2,OK,*5F\r\n

When robot motion executed PTP() targetP2, because of QueueTag(4) , it will return

> $***TMSTA***,10,01,04,true,*61\r\n // TMSTA SubCmd 01, TagNumber 04, completed

* $TMSCT,4,2,OK is returned when the process executed the script. Therefore, if using QueueTag to wait or WaitQueueTag to wait, it will return after the execution as well.

13.4 StopAndClearBuffer()

Stop the motion of the robot and clear existing commands of the robot in the buffer.

Syntax

bool **StopAndClearBuffer**(
)

Parameter

void No parameter

Return

bool True Command accepted； False Command rejected

Note

StopAndClearBuffer()

13.5 ChangeBase()

Set the reference base for the consecutive motion.

Syntax 1

bool **ChangeBase**(
    string,
    int
)

Parameters

string	The base name	
int	The base index. Users can specify the bases created by the vision task of one shot get all. The value is 0 .... N, and the default is 0.	

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Syntax 2

bool **ChangeBase**(
    string
)

Note

Same as syntax 1 and fill 0 as the default base index.

```
ChangeBase("RobotBase")          //change the reference base for motion to "RobotBase"
ChangeBase("vision_job1", 1)     //change the reference base to the 2nd base value of "vision_job1". If the name or the index specified of the base does exist, it reports an error.
ChangeBase("RobotBase", 10)      //change the reference base for motion to "RobotBase". Since it is the name of the base, the base index is invalid.
```

Syntax 3

bool **ChangeBase**(
float[]
)

Parameters

float[]	Base parameters X, Y, Z, RX, RY, and RZ	

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

```
float[] Base1 = {20,30,10,0,0,90}      //declare a floating point array for the base values.
ChangeBase(Base1)      //change the reference base for motion to the set base value
```

Syntax 4

bool **ChangeBase**(
float, float, float, float, float, float
)

Parameters

float, float, float, float, float, float	Base parameters X, Y, Z, RX, RY, and RZ	

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

```
ChangeBase(20,30,10,0,0,90)      //change the reference base to {20,30,10,0,0,90}
```

13.6 ChangeTCP()

Set the end tool parameters for the consecutive motion.

Syntax 1

bool **ChangeTCP**(
string
)

Parameters

string TCP name

Return

bool True Change successfully.
False Change unsuccessfully.

Note

ChangeTCP("RobotEndFlange") //change the end tool to "RobotEndFlange"

Syntax 2

bool **ChangeTCP**(
float[]
)

Parameters

float[] TCP parameters X, Y, Z, RX, RY, and RZ

Return

bool True Change successfully.
False Change unsuccessfully.

Note

```
float[] Tool1 = {0,0,150,0,0,90}  // declare a floating point array for the end tool values.
ChangeTCP(Tool1)                  // change the end tool value to the set end tool value
```

Syntax 3

bool **ChangeTCP**(
float[],
float
)

Parameters

float[] TCP parameters X, Y, Z, RX, RY, and RZ
float TCP mass

Return

bool True Change successfully.
False Change unsuccessfully.

Note

```
float[] Tool1 = {0,0,150,0,0,90}  // declare a floating point array for the end tool values.
ChangeTCP(Tool1,2)                // change the end tool value to the set end tool value.
                                  The weight of the end tool is 2kg.
```

Syntax 4

bool **ChangeTCP**(
float[],
float,
float[]

)

Parameters

float[]	TCP parameters X, Y, Z, RX, RY, and RZ
float	TCP mass
float[]	TCP rotation inertia includes nine values: (1) Ixx, (2) Iyy, (3) Izz, along with the mass center coordinates relative to the tool coordinates, which are (4) X, (5) Y, (6) Z, (7) RX, (8) RY, (9) RZ.

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

```
float[] Tool1 = {0,0,150,0,0,90}          // declare a floating point array for the end tool values.
float[] COM1 = {2,0.5,0.5,0,0,-80,0,0,0}  // declare a floating point array for the rotation inertia and the reference coordinate relative to the tool coordinates.
ChangeTCP(Tool1,2,COM1)                   // change the end tool value to the set end tool value. The weight of the end tool is 2kg,.and it applies the rotation inertia and its reference base.
```

Syntax 5

bool **ChangeTCP**(
float, float, float, float, float, float
)

Parameters

float, float, float, float, float, float	TCP parameters X, Y, Z, RX, RY, and RZ

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

```
ChangeTCP(0,0,150,0,0,90)    // change the end tool value to {0,0,150,0,0,90}
```

Syntax 6

bool **ChangeTCP**(
float, float, float, float, float, float,
float
)

Parameters

float, float, float, float, float, float
TCP parameters X, Y, Z, RX, RY, and RZ
float TCP mass

Return

bool True Change successfully.
False Change unsuccessfully.

Note

ChangeTCP(0,0,150,0,0,90,2) // change the end tool value to {0,0,150,0,0,90}. The weight of the end tool is 2kg.

Syntax 7

bool **ChangeTCP**(
float, float, float, float, float, float,
float,
float, float, float, float, float, float, float, float, float
)

Parameters

float, float, float, float, float, float
TCP parameters X, Y, Z, RX, RY, and RZ
float TCP mass
float, float, float, float, float, float, float, float, float
TCP rotation inertia includes nine values: (1) Ixx, (2) Iyy, (3) Izz, along with the mass center coordinates relative to the tool coordinates, which are (4) X, (5) Y, (6) Z, (7) RX, (8) RY, (9) RZ.

Return

bool True Change successfully.
False Change unsuccessfully.

Note

ChangeTCP(0,0,150,0,0,90,2, 2,0.5,0.5,0,0,-80,0,0,0) // change the end tool value to {0,0,150,0,0,90}. The weight of the end tool is 2kg. The rotation inertia is {2,0.5,0.5} and its reference coordinate is {0,0,-80,0,0,0}.

13.7 ChangeLoad()

Set the load weight to compensate.

Syntax 1

bool **ChangeLoad**(
    float
)

Parameters

float	Load weight in kilograms	

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

ChangeLoad(2.3) // Set the load weight to 2.3 kg.

Syntax 2

bool **ChangeLoad**(
    float,
    float
)

Parameters

float	Load weight in kilograms
float	Weight Conversion Estimated Distance in millimeters

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

ChangeLoad(2.3, 100) // Set the load weight to 2.3 kg.

Syntax 3

bool **ChangeLoad**(
    string,
    int,
    float
)

Parameters

string	the name of the sensor	
int	the sensing condition	
	0	Picking up unknown load
	1	Releasing unknown load
float	Weight Conversion Estimated Distance in millimeters	

Return

bool	True	Change successfully.
	False	Change unsuccessfully.

Note

FTSensor fts1 = " TMFT300"
ChangeLoad("fts1", 0, 100) // Use sensor fts1 to pick up an unknown load and change the load weight by the detected weight.

13.8 PTP()

Define and send PTP motion command into buffer for execution.

Syntax 1

bool **PTP**(
string,
float[],
int,
int,
int,
bool
)

Parameters

string Definition of data format, combines three letters
#1: Motion target format:
"C" expressed in Cartesian coordinate
"J" expressed in joint angles
#2: Speed format:
"P" expressed as a percentage
#3: Blending format
"P" expressed as a percentage

float[] Motion target. If defined with coordinate, it includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°). If defined with joint angle, it includes the angles of six joints: Joint1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°).

int The robot end moving speed setting, expressed as a percentage (%)
≥0 Percentage of speed (%)
-1 Using the Acceleration Table (supported on TM Robot S series models)
<0 Invalid value

int The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.

int Blending value, expressed as a percentage (%)

bool Disable precise positioning
true Disable precise positioning
false Enable precise positioning

Return

bool True Command accepted; False Command rejected (format error)

Note

Data format parameter includes: (1) "CPP", (2) "JPP"

```
float[] target1 = {0,0,90,0,90,0}
PTP("JPP",target1,10,200,0,false)  // variable ingress available
PTP("JPP",{0,0,90,0,90,0},10,200,0,false)  // array constant ingress available
PTP("CPP",Point["P2"].Value,10,200,0,false) // point coordinate retrieving with point parameterization available (robot posture attention required)
PTP("JPP",Point["P2"].Joint,10,200,0,false) // joint angle retrieving with point parameterization available
// move to target with PTP, speed = 10%, time to top speed = 200ms
```

Syntax 2

bool **PTP**(
string,
float[],
int,
int,
int,
bool,
int[]
)

Parameters

string	Definition of data format, combines three letters #1: Motion target format: "C" expressed in Cartesian coordinate #2: Speed format: "P" expressed as a percentage #3: Blending format "P" expressed as a percentage
float[]	Motion target. If defined with coordinate, it includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°).
int	The robot end moving speed setting, expressed as a percentage (%) ≥0 Percentage of speed (%) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
int	Blending value, expressed as a percentage (%)
bool	Disable precise positioning true Disable precise positioning false Enable precise positioning
int[]	The pose of robot : [Config1, Config2, Config3], please find more information in appendix

Return

bool True Command accepted; False Command rejected (format error)

Note

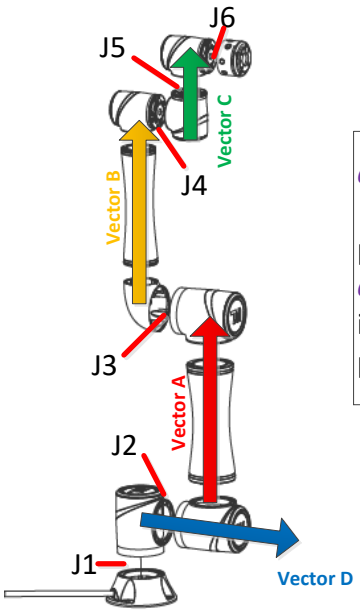
Data format parameter includes: (1) "CPP"

```
float[] targetP1 = {417.50,-122.30,343.90,180.00,0.00,90.00}
float[] pose = {0,2,4}

PTP("CPP", target1,50,200,0,false, pose)          // variable ingress available
PTP("CPP",{417.50,-122.30,343.90,180.00,0.00,90.00},10,200,0,false,pose)
                                                  // array constant ingress available
PTP("CPP",{417.50,-122.30,343.90,180.00,0.00,90.00},10,200,0,false,{0,2,4})
                                                  // array constant ingress available
PTP("CPP",Point["P2"].Value,10,200,0,false,{0,2,4}) // point coordinate retrieving with point
                                                  parameterization available
                                                  // move to target with PTP, speed = 10%, time
```

to top speed = 200ms, and pose configuration = 024.

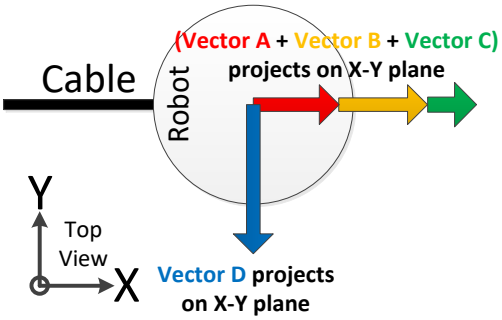
- **Pose Configuration Parameters: [Config1, Config2, Config3]**



Config: config1, config2, config3

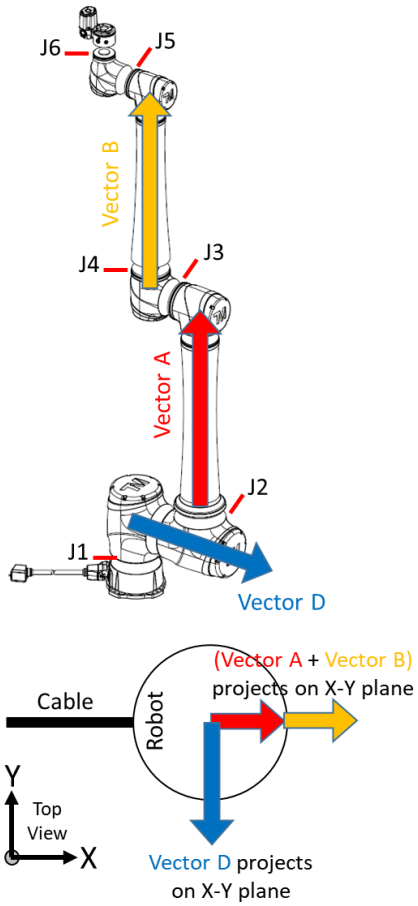
config1=0:
if [(Vector A + Vector B + Vector C) projects on X-Y plane] cross [Vector D projects on X-Y plane] is on negative-Z
config1=1:
if [(Vector A + Vector B + Vector C) projects on X-Y plane] cross [Vector D projects on X-Y plane] is on positive-Z

config2=2:
if (config1=0 and J3 is positive) or (config1=1 and J3 is negative)
config2=3:
if (config1=0 and J3 is negative) or (config1=1 and J3 is positive)



config3=4:
if (config1=0 and J5 is positive) or (config1=1 and J5 is negative)
config3=5:
if (config1=0 and J5 is negative) or (config1=1 and J5 is positive)

TM25S/TM30S



config1=0:
if [(Vector A + Vector B) projects on X-Y plane] cross [Vector D projects on X-Y plane] is on negative-Z
config1=1:
if [(Vector A + Vector B) projects on X-Y plane] cross [Vector D projects on X-Y plane] is on positive-Z

config2=2:
if (config1=0 and J3 is positive) or (config1=1 and J3 is negative)
config2=3:
if (config1=0 and J3 is negative) or (config1=1 and J3 is positive)

config3=4:
if (config1=0 and J5 is positive) or (config1=1 and J5 is negative)
config3=5:
if (config1=0 and J5 is negative) or (config1=1 and J5 is positive)

Syntax 3

```
bool PTP(
    string,
    float[],
    int,
    int,
    int,
    bool,
    float[],
)
```

Parameters

string	Definition of data format, combines three letters #1: Motion target format: "C" expressed in coordinate #2: Speed format: "P" expressed as a percentage #3: Blending format: "P" expressed as a percentage
float[]	Motion target expressed in coordinate, It is six elements of the TCP coordinate at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°).
int	The robot end moving speed setting, expressed as a percentage (%) ≥0 Percentage of speed (%)

-1 Using the Acceleration Table (supported on TM Robot S series models)
<0 Invalid value

int The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.

int Blending value, expressed as a percentage (%)

bool Disable precise positioning
true Disable precise positioning
false Enable precise positioning

float[] Motion target expressed in reference joint angles. It is six elements of the robot joints: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°).

Return

bool True Command accepted; False Command rejected

Note

Data format parameter includes: (1) "CPP"

```
float[] target1 = {417.50,-122.30,343.90,180.00,0.00,90.00}
float[] joint6 = {3.53,-13.26,116.3,-13.04,90,3.53}

PTP("CPP",target1,10,200,0,false,joint6)                    // variable ingress available
PTP("CPP",{417.50,-122.30,343.90,180.00,0.00,90.00},10,200,0,false,joint6)
                                                            // array constant ingress available
PTP("CPP",{417.50,-122.30,343.90,180.00,0.00,90.00},10,200,0,false,{3.53,-
                                                            13.26,116.3,-13.04,90,3.53})
PTP("CPP",Point["P2"].Value,10,200,0,false,Point["P2"].Joint)
                                                            // point coordinate retrieving with point
                                                            parameterization available
                                                            // move to target with PTP, speed = 10%,
                                                            time to top speed = 200ms, and attempt to
                                                            reach the closest assigned joint target.
```

13.9 Move_PTP()

Define and send PTP relative motion commands for execution.

Syntax 1

bool **Move_PTP**(
string,
float[],
int,
int,
int,
bool
)

Parameters

string	Definition of data format made of three letters #1: Relative motion target format: "C": expressed with the current robot base "T": expressed with the tool coordinate "J": expressed in joint angles #2: Speed format: "P": expressed as a percentage #3: Blending format: "P": expressed as a percentage
float[]	relative motion parameters. If expressed in coordinate, it includes the robot end TCP relative motion value with respect to the specified coordinate: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°); If defined with joint angle, it includes the angles of six joints: Joint1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°)
int	The robot end moving speed setting, expressed as a percentage (%) ≥0 Percentage of speed (%) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
int	Blending value, expressed as a percentage (%)
bool	Disable precise positioning true Disable precise positioning false Enable

Return

bool	True Command accepted; False Command rejected (format error)

Note

Motion command parameter includes: (1) "CPP", (2) "TPP" or (3) "JPP"

```
float[] relmove = {0,0,10,45,0,0}
Move_PTP("TPP",var_rel,10,200,0,false)          // variable ingress available
Move_PTP("TPP",{0,0,10,45,0,0},10,200,0,false) // array constant ingress available
// Move 0,0,10,45,0,0, with respect to tool coordinate, with PTP, velocity = 10%, time to top speed = 200ms
```

13.10 Line()

Define and send Line motion command into buffer for execution.

Syntax 1

bool **Line**(
string,
float[],
int,
int,
int,
bool
)

Parameters

string Definition of data format, combines three letters
#1: Motion target format:
"C" expressed with Cartesian coordinate
#2: Speed format:
"P" expressed by percentage
"A" expressed with absolute speed and in synchronization with the project speed
"D" expressed with absolute speed and not in synchronization with the project speed
#3: Blending format:
"P" expressed by percentage
"R" expressed by radius

float[] Motion target. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)

int The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s)
≥0 Percentage of speed (%) or absolute speed (mm/s)
-1 Using the Acceleration Table (supported on TM Robot S series models)
<0 Invalid value

int The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.

int Blending value, expressed as a percentage (%) or in radius (mm)

bool Disable precise positioning
true Disable precise positioning
false Enable precise positioning

Return

bool True Command accepted; False Command rejected (format error)

Note

Data format parameter includes:

```
float[] target1 = {417.50,-122.30,343.90,180.00,0.00,90.00}
Line("CAR",target1,100,200,50,false)    // variable ingress available
Line("CAR",{417.50,-122.30,343.90,180.00,0.00,90.00},100,200,50,false)
                                        // array constant ingress available
```

```
Line("CAR",Point["P2"].Value,100,200,50,false)
// point coordinate retrieving with point parameterization available
// move to target with Line, speed = 10%, time to top speed = 200ms, and blending value = 50

// Opt for the singularity handling mechanism set by LineSingularity().
LineSingularity(0)      // Disable singularity handling.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Disable
Line("CPP", {138.0930,-411.4636,438.1152,89.5760,-0.3520,0.4868}, 100, 500, 0, false)
// Disable, through singularity

LineSingularity(1)      // Enable singularity handling: path avoidance.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Enable
Line("CPP", {138.0930,-411.4636,438.1152,89.5760,-0.3520,0.4868}, 100, 500, 0, false)
// Enable, path avoidance
```

Syntax 2

```
bool Line(
    string,
    float[],
    int,
    int,
    int,
    bool,
    int
)
```

Parameters

string	Definition of data format, combines three letters #1: Motion target format: "C" expressed with Cartesian coordinate #2: Speed format: "P" expressed by percentage "A" expressed with absolute speed and in synchronization with the project speed "D" expressed with absolute speed and not in synchronization with the project speed #3: Blending format: "P" expressed by percentage "R" expressed by radius
float[]	Motion target. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
int	The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s) ≥0 Percentage of speed (%) or absolute speed (mm/s) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.

int Blending value, expressed as a percentage (%) or in radius (mm)
bool Disable precise positioning
true Disable precise positioning
false Enable precise positioning
int Singularity handling.
0 Disbale
1 Path avoidance
2 Speed change (TM25S, TM30S)
* After exiting from the function, the singularity handling mechanism returns to what it was before entering.

Return

bool True Command accepted; False Command rejected (format error)

Note

Data format parameter includes:
(1) "CPP", (2) "CPR", (3) "CAP", (4) "CAR", (5) "CDP", (6) "CDR"

Line("CAR", 417.50,-122.30,343.90,180.00,0.00,90.00,100,200,50,false)

// Move to 417.50,-122.30,343.90,180.00,0.00,90.00 with Line, velocity = 100mm/s, time to top speed = 200ms, blending radius = 50mm

13.11 Move_Line()

Define and send Line relative motion commands for execution.

Syntax 1

bool **Move_Line**(
string,
float[],
int,
int,
int,
bool
)

Parameters

string Definition of data format made of three letters
#1: Relative motion target format:
"C": expressed with w.r.t. current base
"T": expressed with w.r.t. tool coordinate
#2: Speed format:
"P": expressed by percentage
"A" expressed with absolute speed and in synchronization with the project speed
"D" expressed with absolute speed and not in synchronization with the project speed
#3: Blending format:
"P": expressed by percentage
"R": expressed by radius

float[] Relative motion parameters. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)

int The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s)
≥0 Percentage of speed (%) or absolute speed (mm/s)
-1 Using the Acceleration Table (supported on TM Robot S series models)
<0 Invalid value

int The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.

int Blending value, expressed as a percentage (%) or in radius (mm)

bool Disable precise positioning
true Disable precise positioning
false Enable

Return

bool True Command accepted; False Command rejected (format error)

Note

Motion command parameter includes: (1) "CPP", (2) "CPR", (3) "CAP", (4) "CAR", (5) "CDP", (6) "CDR", (7) "TPP", (8) "TPR", (9) "TAP", (10) "TAR", (11) "TDP", (12) "TDR"

```
float[] var_rel= {0, 0, 10, 25, 0, 0}
Move_Line("TAP",var_rel,125,200,0,false)          // variable ingress available
Move_Line("TAP",{0,0,10,25,0,0},125,200,0,false)  // array constant ingress available
```

```
// move to target with Line, velocity = 125mm/s, time to top speed = 200ms

// Opt for the singularity handling mechanism set by LineSingularity().
LineSingularity(0)      // Disable singularity handling.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Disable
Move_Line("CPP", {0,-300,0,0,0,0}, 100, 500, 0, false) // Disable, through singularity

LineSingularity(1) // Enable singularity handling: path avoidance.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Enable
Move_Line("CPP", {0,-300,0,0,0,0}, 100, 500, 0, false) // Enable, path avoidance
```

Syntax 2

```
bool Move_Line(
    string,
    float[],
    int,
    int,
    int,
    bool,
    int
)
```

Parameters

string	Definition of data format made of three letters #1: Relative motion target format: "C": expressed with w.r.t. current base "T": expressed with w.r.t. tool coordinate #2: Speed format: "P": expressed by percentage "A" expressed with absolute speed and in synchronization with the project speed "D" expressed with absolute speed and not in synchronization with the project speed #3: Blending format: "P": expressed by percentage "R": expressed by radius
float[]	Motion target. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
int	The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s) ≥0 Percentage of speed (%) or absolute speed (mm/s) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
int	Blending value, expressed as a percentage (%) or in radius (mm)
bool	Disable precise positioning

true Disable precise positioning
false Enable

int Singularity handling.
0 Disbale
1 Path avoidance
2 Speed change (TM25S, TM30S)
* After exiting from the function, the singularity handling mechanism returns to what it was before entering.

Return

bool True Command accepted； False Command rejected (format error)

Note

Motion command parameter includes: (1) "CPP", (2) "CPR", (3) "CAP", (4) "CAR", (5) "CDP", (6) "CDR", (7) "TPP", (8) "TPR", (9) "TAP", (10) "TAR", (11) "TDP", (12) "TDR"

```
// Opt for the singularity handling mechanism set by LineSingularity().
LineSingularity(0)     // Disable singularity handling.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Disable
Move_Line("CPP", {0,-300,0,0,0,0}, 100, 500, 0, false) // Disable, through singularity

LineSingularity(1) // Enable singularity handling: path avoidance.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Enable
Move_Line("CPP", {0,-300,0,0,0,0}, 100, 500, 0, false) // Enable, path avoidance
```

13.12 Circle()

Define and send Circle motion command into buffer for execution.

Syntax 1

bool **Circle**(
string,
float[],
float[],
int,
int,
int,
int,
bool
)

Parameters

string	Definition of data format, combines three letters #1: Motion target format: "C" expressed with Cartesian coordinate #2: Speed format: "P" expressed by percentage "A" expressed with absolute speed and in synchronization with the project speed "D" expressed with absolute speed and not in synchronization with the project speed #3: Blending format: "P" expressed by percentage
float[]	A point on arc. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
float[]	The end point of arc. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
int	The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s) ≥0 Percentage of speed (%) or absolute speed (mm/s) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
int	Blending value, expressed as a percentage (%)
int	Arc angle(°), If non-zero value is given, the TCP will keep the same pose and move from current point to the assigned arc angle via the given point and end point on arc; If zero is given, the TCP will move from current point and pose to end point and pose via the point on arc with linear interpolation on pose.
bool	Disable precise positioning true Disable precise positioning false Enable precise positioning

Return

bool	True Command accepted; False Command rejected (format error)

Note

Data format parameter includes: (1) "CPP", (2) "CAP", (3) "CDP"

PTP("JPP", {0, 0, 90, 0, 90, 0}, -1, 500, 0, false**)**

```
float[] targetPass= {417.50,-122.30,343.90,180.00,0.00,90.00}
float[] targetEnd= {381.70,208.74,343.90,180.00,0.00,135.00}
Circle("CAP",targetPass,targetEnd,100,200,50,270,false)        // variable ingress available
Circle("CAP",targetPass,{381.7,208.74,343.9,180,0,135},100,200,50,270,false)
// array constant ingress available
Circle("CAP",Point["P1"].Value,{381.7,208.74,343.9,180,0,135},100,200,50,270,false)

// point coordinate retrieving with point parameterization available
// Move on 270° arc, velocity = 100mm/s, time to top speed = 200ms, blending value = 50%
```

Syntax 2

```
bool Circle(
    string,
    float[],
    float[],
    int,
    int,
    int,
    int,
    int,
    bool
)
```

Parameters

string	Definition of data format, combines three letters #1: Motion target format: "C" expressed with Cartesian coordinate #2: Speed format: "P" expressed by percentage "A" expressed with absolute speed and in synchronization with the project speed "D" expressed with absolute speed and not in synchronization with the project speed #3: Blending format: "P" expressed by percentage
float[]	A point on arc. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
float[]	The end point of arc. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)
int	The robot end moving speed setting, expressed as a percentage (%) or an absolute speed (mm/s) ≥0 Percentage of speed (%) or absolute speed (mm/s) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value

int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
int	Blending value, expressed as a percentage (%)
int	Arc angle(°), If non-zero value is given, the TCP will keep the same pose and move from current point to the assigned arc angle via the given point and end point on arc; If zero is given, the TCP will move from current point and pose to end point and pose via the point on arc with linear interpolation on pose.
int	Rotation 0 Linear Interpolation 1 Keep Rotation
bool	Disable precise positioning true Disable precise positioning false Enable precise positioning

Return

bool	True Command accepted; False Command rejected (format error)

Note

Data format parameter includes: (1) "CPP", (2) "CAP", (3) "CDP"

```
float[] targetPass= {417.50,-122.30,343.90,180.00,0.00,90.00}
float[] targetEnd= {381.70,208.74,343.90,180.00,0.00,135.00}

PTP("JPP", {0, 0, 90, 0, 90, 0}, -1, 500, 0, false)
Circle("CAP",targetPass,targetEnd,100,200,50,270,false)
Circle("CAP",targetPass,targetEnd,100,200,50,270,1,false)
// Move on 270° arc, rotation = keep rotation

PTP("JPP", {0, 0, 90, 0, 90, 0}, -1, 500, 0, false)
Circle("CAP",targetPass,targetEnd,100,200,50,0,false)
Circle("CAP",targetPass,targetEnd,100,200,50,0,0,false)
// Move on the reach end point arc, rotation = linear interpolation

PTP("JPP", {0, 0, 90, 0, 90, 0}, -1, 500, 0, false)
Circle("CAP",targetPass,targetEnd,100,200,50,270,0,false)
// Move on 270° arc, rotation = linear interpolation

PTP("JPP", {0, 0, 90, 0, 90, 0}, -1, 500, 0, false)
Circle("CAP",targetPass,targetEnd,100,200,50,0,1,false)
// Move on the reach end point arc, rotation = keep rotation
```

13.13 PLine()

Define and send PLine motion command into buffer for execution.

Syntax 1

bool **PLine**(
string,
float[],
int,
int,
int
)

Parameters

string Definition of data format, combines three letters
#1: Motion target format:
"J": expressed with joint angles
"C": expressed with Cartesian coordinate
#2: Speed format:
"A" expressed with absolute speed and in synchronization with the project speed
"D" expressed with absolute speed and not in synchronization with the project speed
#3: Blending format:
"P": expressed by percentage

float[] Motion target. If expressed in joint angles, it includes the angles of six joints: Joint1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), Joint 6(°)；If expressed in coordinate, it includes the the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)

int The robot end moving speed setting, expressed as an absolute speed (mm/s)

int The time interval to accelerate to top speed (ms)

int Blending value, expressed as a percentage (%)

Return

bool True Command accepted； False Command rejected (format error)

Note

Data format parameter includes: (1) "CAP", (2) "CDP", (3) "JAP", (4) "JDP"

```
float[] targetP1 = {417.50,-122.30,343.90,180.00,0.00,90.00}
PLine("CAP",target1,100,200,50) // variable ingress available
PLine("CAP",{417.50,-122.30,343.90,180.00,0.00,120.00},100,200,50)
// array constant ingress available
PLine("CAP",Point["P1"].Value,100,200,50)
// point coordinate retrieving with point parameterization available
// move to target with PLine, speed = 100mm/s, time to top speed = 200ms, and blending value = 50
```

13.14 Move_PLine()

Define and send PLine relative motion commands for execution.

Syntax 1

bool **Move_PLine**(
string,
float[],
int,
int,
int
)

Parameters

string Definition of data format made of three letters
#1: Relative motion target format:
"C": expressed with w.r.t. current base
"T": expressed with w.r.t. tool coordinate
"J": expressed with joint angles
#2: Speed format:
"A" expressed with absolute speed and in synchronization with the project speed
"D" expressed with absolute speed and not in synchronization with the project speed
#3: Blending format:
"P": expressed by percentage

float[] Relative motion parameters expressed in coordinate. It includes the coordinate of tool center point at the robot end: X (mm), Y (mm), Z (mm), RX(°), RY(°), RZ(°)

int The robot end moving speed setting, expressed as an absolute speed (mm/s)

int The time interval to accelerate to top speed (ms)

int Blending value, expressed as a percentage (%)

Return

bool True Command accepted; False Command rejected (format error)

Note

Motion command parameter includes:
(1) "CAP", (2) "CDP", (3) "TAP", (4) "TDP", (5) "JAP", (6) "JDP"

```
float[] var_rel= {0, 0, 10, 25, 0, 0}
Move_PLine("CAP",var_rel,125,200,0)                    // variable ingress available
Move_PLine("CAP",{0,0,10,25,0,0},125,200,0)            // array constant ingress available
// move relatively to target with PLine, speed = 125mm/s, time to top speed = 200ms
```

13.15 LineSingularity()

Set the line motion control with singularity handling or not.

Syntax 1

bool **LineSingularity**(
    int
)

Parameters

int	Singularity handling.	
	0	Disbale
	1	Path avoidance
	2	Speed change (TM25S, TM30S)

Return

bool True Command accepted; False Command rejected

Note

When the project is running, it defaults to 0 to disable. Once configured, it will affect the line motion control used later.

```
LineSingularity(0)      // Disable singularity handling.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Disable
Line("CPP", {138.0930,-411.4636,438.1152,89.5760,-0.3520,0.4868}, 100, 500, 0, false)
// Disable, through singularity

LineSingularity(1)      // Enable singularity handling: path avoidance.
PTP("JPP", {45,-20,125,-100,-15,0}, 100, 500, 0, false)
Line("CPP", {307.8192,-100.8191,436.7351,90.1633,-0.4788,0.4848}, 100, 500, 0, false)
// Enable
Line("CPP", {138.0930,-411.4636,438.1152,89.5760,-0.3520,0.4868}, 100, 500, 0, false)
// Enable, path avoidance
```

13.16 CollisionCheck()

Pre-collision checks help prevent robots from interfering with self-testing and avoid collisions between the gripper and the box. By adjusting and modifying the exported scene from TMstudio or using the built-in box container in TMvision, users can simulate robot motions using robot parts, tools, and virtual boxes. This simulation allows for early detection of potential issues during motions, reducing collisions in applications like box picking, using large hardware, and executing critical poses.

Syntax 1

string **CollisionCheck**(
    float,
    string
)

Parameter

float	Safety distance (mm)
string	The subflow name. For use in flow projects only. Returns errors if using in script projects.

Return

string	the result of checking	
	== ""	The value returned is an empty string, and there was no collision detected.
	!= ""	The value returned is a non-empty string, and there was a collision detected. The contest will indicate which node.

Syntax 2

string **CollisionCheck**(
    float,
    ?
)

Parameter

float	Safety distance (mm)
?	The target motion to check. It can be a statement or a self-defined function.

Return

string	the result of checking	
	== ""	The value returned is an empty string, and there was no collision detected.
	!= ""	The value returned is a non-empty string, and there was a collision detected. The contest will indicate which line number.

* Check motion functions PTP(), Move_PTP(), Line(), Move_Line(), and Circle() only.
* Support variable operations, general functions, math functions, and parameterized objects (read only) only. Does not operate with other functions.
* The result of the variable operation is vaild only during the pre-checking. The values revert to the default after checking.
* All statements within the conditional expression will be checked.
* All statements within the loop expression will be checked only once and will not repeat.

Note

(1)

```
string result = CollisionCheck(15, "CCheck0")
// Check subflow CCheck0 (use only in Flow projects)
(2)
define
{
    TPoint P2 = {516.65,-147.75,445.37,179.44,-0.32,89.91},{0,0,90,0,90,0}
    TPoint P3 =
{516.14,156.17,443.43,179.59,0.30,111.24},{32.92,0.26,89.95,0,89.30,11.58}
    TPoint P4 = {446.79,-313.56,435.31,-179.58,0.24,90.22},{-19.17,1.39,89.79,-
    0.32,89.31,-19.49}
    ModbusTCP localhost = 127.0.0.1,502
    int count = 0
}
main
{
    Display(count)              // count = 0
    Pause()
    string re = CollisionCheck(15, TargetMotion())
    // Set safety distance to 15 mm for TargetMotion() function to check
    if (re == "") TargetMotion()// No collision detected. Call TargetMotion() for the real operation.
    else Display("Collision: " + re)  // Collistion detected.
    Display(count)                    // count = 0 or 1
    // +1 during pre-checking. Revert to the default, 0, after checking. If no collision detected, it calls the
    function TargetMotion(), and the the count value is 1. If collision detected, it does not call the function
    TargetMotion(), and the the count value is 0.
}
void TargetMotion()
{
    count++      // count = 1      // Support variable operation during pre-checking.
    while (true)  // The loop expression will be checked once only during pre-checking.
    {
        PTP("CPP",Point["P2"].Value,50,200,100,false)          // check
        // check only during pre-checking without motion
        PTP("JPP",Point["P3"].Joint,50,200,100,false)          // check
        Move_PTP("JPP",{0,0,0,0,0,60},50,200,100,false)        // check
        Line("CPP",Point["P4"].Value,50,200,100,false)         // check
        Move_Line("CPP", {20,20,20,0,0,0},50,200,100,false)// check
        Circle("CPP", Point["P2"].Value, Point["P3"].Value, 50, 200, 100, 100, false)
        // check
        WaitQueueTag() // ignore // Do not support to this function during pre-checking.
        byte[] bb = modbus_read("localhost", 1, "DO", 0, 10)
        // ignore // Do not support to this function during pre-checking.
        string ss = GetString(bb)  // General function. The operation result is ss = "{}".
    }
}
```

13.17 PVTEnter()

Set PVT mode to start with Joint/Cartesian command

Syntax 1

bool **PVTEnter**(
int
)

Parameter

int PVT Mode
0 Joint
1 Cartesian

Return

bool True Command accepted; False Command rejected

Note

Syntax 2

bool **PVTEnter**(
)

Parameter

Void No parameter. Use PVT mode with Joint Command by default.

Return

bool True Command accepted; False Command rejected

Note

PVTEnter(1)

* Before switching to PVT mode, it waits for other robot motion instructions to complete.
* When the PVT mode begins, it only supports to functions tied to PVT, QueueTag, IO, and Payload.

13.18 PVTExit()

Set PVT mode motion to exit

Syntax 1

bool **PVTExit**(
)

Parameter

void No parameter

Return

bool True Command accepted; False Command rejected

Note

PVTExit()

* After exiting PVT mode, it waits for PVT function motion instructions to complete.

13.19 PVTPoint()

Set the PVT mode parameters of motion in position, velocity, and duration.

Syntax 1

bool **PVTPoint**(
float[],
float[],
float,
bool
)

Parameter

float[]	Target position {J1, J2, J3, J4, J5, J6} in PVT mode with Joint {X, Y, Z, RX, RY, RZ} in PVT mode with Cartesian
float[]	Target velocity {J1, J2, J3, J4, J5, J6}' in PVT mode with Joint {X, Y, Z, RX, RY, RZ}' in PVT mode with Cartesian
float	Duration (second), it requires ≧ 0.01 seconds.
bool	Synchronize to the project speed or not.
true	Synchronize to the project speed
false	Not synchronize to the project speed

Return

bool	True Command accepted; False Command rejected

Note

Syntax 2

bool **PVTPoint**(
float[],
float[],
float
)

Note

Same as Syntax 1. It default true to synchronize to the project speed or not.

Syntax 3

bool **PVTPoint**(
float, float, float, float, float, float,
float, float, float, float, float, float,
float,
bool
)

Parameter

float, float, float, float, float, float,	Target Position. {J1, J2, J3, J4, J5, J6} in PVT mode with Joint

{X, Y, Z, RX, RY, RZ} in PVT mode with Cartesian

float, float, float, float, float, float,
Target Velocity.
{J1, J2, J3, J4, J5, J6}' in PVT mode with Joint
{X, Y, Z, RX, RY, RZ}' in PVT mode with Cartesian

float Duration (second), it requires ≧ 0.01 seconds.

bool Synchronize to the project speed or not.
true Synchronize to the project speed
false Not synchronize to the project speed

Return

bool True Command accepted; False Command rejected

Note

PVTEnter(1)
PVTPoint(467.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,0.5)
PVTPoint(467.5,-72.2,359.7,180,0,90,-50,50,0,0,0,0,0.5)
PVTPoint(417.5,-72.2,359.7,180,0,90,0,0,0,0,0,0,0.5)
PVTPoint(417.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,0.5)
PVTPoint(417.5,-122.2,359.7,180,0,60,50,50,0,0,0,0,3)
PVTPoint(417.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,3)
PVTExit()

Syntax 4

bool **PVTPoint**(
float, float, float, float, float, float,
float, float, float, float, float, float,
float
)

Note

Same as Syntax 3. It default true to synchronize to the project speed or not.

PVTEnter(1)
PVTPoint(467.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,0.5)
PVTPoint(467.5,-72.2,359.7,180,0,90,-50,50,0,0,0,0,0.5)
PVTPoint(417.5,-72.2,359.7,180,0,90,0,0,0,0,0,0,0.5, true)
PVTPoint(417.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,0.5, false)
PVTPoint(417.5,-122.2,359.7,180,0,60,50,50,0,0,0,0,3, false)
PVTPoint(417.5,-122.2,359.7,180,0,90,50,50,0,0,0,0,3)
PVTExit()

13.20 PVTPause()

Set PVT mode motion to pause

Syntax 1

bool **PVTPause**(
)

Parameter

void	No parameter

Return

bool	True Command accepted; False Command rejected

Note

PVTPause()

13.21 PVTResume()

Set PVT mode motion to resume

Syntax 1

bool **PVTResume**(
)

Parameter

void	No parameter

Return

bool	True Command accepted; False Command rejected

Note

PVTResume()

13.22 PathOffset_Set()

Set Path Offset parameters

Syntax 1

bool **PathOffset_Set**(
bool,
float[],
int,
float
)

Parameter

bool Enable Path Offset or not.
false Disable
true Enable

float[] Offset values in coordinate for the six elements of the robot coordinate: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

int Offset reference base
0 the robot base
1 tool (default)
2 the current base
3 trajectory

float Alpha filter coefficient value ranging from 0 to 1. The lesser the value is, the slower the offset compensate speed is. In practical use, it is best to start testing at a lower setting, such as 0.05, and gradually increase it to about 0.1 to determine the most suitable value. Also, monitor closely for excessively rapid compensation increases once the setting exceeds 0.5.

* Calling in the flow required.

Return

boolTrue Command accepted; False Command rejected

Syntax 2

bool **PathOffset_Set**(
bool,
float[],
int
)

Note

Parameter definition same as Syntax 1. Setting the enable path offset, the offset values, and the offset reference base without setting the alpha filter coefficient value.

* Calling in the flow required.

Syntax 3

bool **PathOffset_Set**(
bool,
float[]
)

Note

Parameter definition same as Syntax 1. Setting the enable path offset and the offset values by the tool reference base without setting the alpha filter coefficient value.
* Calling in the flow required.

Syntax 4

bool **PathOffset_Set**(
bool,
float
)

Note

Parameter definition same as Syntax 1. Setting the enable path offset and the alpha coefficient without setting the offset values and the alpha filter coefficient value.
* Calling in process required.

Syntax 5

bool **PathOffset_Set**(
bool
)

Note

Parameter definition same as Syntax 1. Setting the enable path offset only without setting the offset values and the alpha filter coefficient value.
* Calling in process required.

Suppose in the Flow page

```
// Enable Path Offset with setting {10,0,0,0,0,0} as the offset value by the tool base and 0.005 to the alpha coefficient.
PathOffset_Set(true, {10,0,0,0,0,0}, 1, 0.005)
PathOffset_Set(false)       // Disable Path Offseting
// Enable Path Offset with setting {10,0,0,0,0,0} as the offset value by the tool base and without setting the alpha coefficient.
PathOffset_Set(true, {10,0,0,0,0,0}, 1)
PathOffset_Set(false)       // Disable Path Offseting
// Enable Path Offset with setting {10,0,0,0,0,0} as the offset value by the tool base and without setting the alpha coefficient.
PathOffset_Set(true, {10,0,0,0,0,0})
PathOffset_Set(false)       // Disable Path Offseting
// Enable Path Offset with setting the offset value and the alpha coefficient.
PathOffset_Set(true)
```

Suppose in the Thread page

```
PathOffset_Set(true, {10,0,0,0,0,0})    // Return Error. Must be in the Flow page to enable or disable Path Offset.
PathOffset_Set(false)                   // Return Error. Must be in the Flow page to enable or disable Path Offset.
```

Syntax 6

bool **PathOffset_Set**(

float[],
int
)

Parameter

float[] Offset values in coordinate for the six elements of the robot coordinate: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

int Offset reference base

0 the robot base

1 tool (default)

2 the current base

3 trajectory

* Calling and setting the offset value and the reference base in the flow or the thread available.

Return

bool True Command accepted; False Command rejected

Syntax 7

bool **PathOffset_Set**(
float[]
)

Note

Parameter definition same as Syntax 6. Setting the offset value by the reference tool base.

Suppose in the Flow page

```
PathOffset_Set(true)                    // Enable Path Offset without setting the offset value and the alpha coefficient.
```

Suppose in the Thread page

```
PathOffset_Set({10,0,0,0,0,0}, 0)       // Set {10,0,0,0,0,0} as the offset value by the robot base.
PathOffset_Set({5,0,0,0,0,0})           // Set {5,0,0,0,0,0} as the offset value by the tool base.
```

13.23 PathOffset_*Get()*

Get the Path Offset values

Syntax 1

float[] **PathOffset_Get**(
int
)

Parameter

int	Get the current offset value.	
	0	Get by the robot base.
	1	Get by the offset reference base. (Default)

Return

float[]	Offset values in coordinate for the six elements of the robot coordinate: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Syntax 2

float[] **PathOffset_Get**(
)

Parameter

void	No input value

Return

float[]	Offset values in coordinate for the six elements of the robot coordinate: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

Note

Same as Syntax 1. Get the offset value by the current offset reference base.

```
// Enable Path Offset with setting {10,0,0,0,0,0} as the offset value by the tool base and 0.005 to the alpha coefficient.
PathOffset_Set(true, {10,0,0,0,0,0}, 1, 0.005)
// It proceeds with offset compensation, whether the robot is moving, once Path Offset is enabled.
// So the current offset value to read tends to the setting offset value continuously.
PathOffset_Get()      // {1.1,0,0,0,0,0}
PathOffset_Get()      // {2.4,0,0,0,0,0}
…
PathOffset_Get()      // {9.999952,0,0,0,0,0}
```

13.24 PathOffset_*IsEnabled()*

Check if the Path Offset enabled.

Syntax 1

bool **PathOffset_IsEnabled**(
)

Parameter

void	No input value

Return

bool	if the Path Offset enabled
false	Disabled
true	Enabled

Note

```
PathOffset_IsEnabled()          // false
PathOffset_Set(true, {10,0,0,0,0,0}, 1, 0.005)
PathOffset_IsEnabled()          // true
```

13.25 *PathOffset_AlphaFilter()*

Set the Alpha Filter coefficient to avoid over-acceleration.

Syntax 1

bool **PathOffset_AlphaFilter**(
    float
)

Parameter

Float	Alpha filter coefficient value ranging from 0 to 1. The lesser the value is, the slower the offset compensate speed is. In practical use, it is best to start testing at a lower setting, such as 0.05, and gradually increase it to about 0.1 to determine the most suitable value. Also, monitor closely for excessively rapid compensation increases once the setting exceeds 0.5.

Return

bool	True Command accepted; False Command rejected

Note

```
PathOffset_Set(true, {10,0,0,0,0,0}, 1, 0.005)
PathOffset_AlphaFilter(0.01)
PathOffset_AlphaFilter(1.2)          // Return false for out of range.
```

13.26 PathOffset_*MaxOffset()*

Set the upper bounds of the distance and the rotation.

Syntax 1

bool **PathOffset_MaxOffset**(
    float,
    float
)

Parameter

float	the distance upper bound in mm
float	the rotation upper bound in degree

Return

bool	True Command accepted; False Command rejected

Note

```
// Set the offet compensation upper bound.
PathOffset_MaxOffset(10, 3)
// Enable Path Offset with setting {20,0,0,0,0,0} as the offset value by the tool base and 0.005 to the alpha coefficient.

PathOffset_Set(true, {20,0,0,0,0,0}, 1, 0.005)
// It proceeds with offset compensation, whether the robot is moving, once Path Offset is enabled.
// So the current offset value to read tends to the setting offset value continuously.
PathOffset_Get()    // {1.1,0,0,0,0,0}
PathOffset_Get()    // {2.4,0,0,0,0,0}
…
PathOffset_Get()    // {9.999952,0,0,0,0,0}
…
PathOffset_Get()    // {9.999952,0,0,0,0,0}    // Set the distance upper bound to 10mm
```

(1) In the Flow project

Flow	Thread

Point Node: P1
Point Node: P2
Script Node: Script1
PathOffset_Set(true)
// Enable Path Offset
Point Node: P3
Script Node: Script2
PathOffset_Set(false)
// Disable Path Offsetting
Point Node: P4
… Link To P1 …
	Script Node: Script3
	// Set the alpha coeffcient
	PathOffset_AlphaFilter(0.005)
	// Set the offset compensation upper bound
	PathOffset_MaxOffset(20, 5)
	// Read the required offset compensation value from mbus1
	var_X = **modbus_read**("mbus1", "offsetX")
	// Offset to the X coordinate
	var_Offset[0] = var_X
	// Update the offset value by the tool base
	PathOffset_Set(var_Offset, 1)
	Goto Node: Goto1
	… Link to Script3 …

● It enables Path Offset when it is on the path of P2 toward P3. ● It disables Path Offset after moving to P3.	● Since the enable and the disable of the Path Offset come in the Flow, it is required to reset the AlphaFilter and the MaxOffset in the Thread. ● Keep updating the offset value in the Thread.

(2) In the Script project

```
define
{
    float var_X = 0
    float[] var_Offset = {0,0,0,0,0,0}
    ModbusTCP mbus1 = "127.0.0.1"
}
main
{
    ThreadRun(Offsetting())
    while (true)
    {
        PTP("JPP",{15,0,90,0,90,0},50,200,100,false)
        PTP("JPP",{15,0,75,0,90,0},50,200,100,false)
        PathOffset_Set(true)        // Enable Path Offset
        PTP("JPP",{-15,0,75,0,90,0},50,200,100,false)
        PathOffset_Set(false)       // Disable Path Offset
        PTP("JPP",{-15,0,90,0,90,0},50,200,100,false)

        Sleep(10)
    }
}
void Offsetting()
{
    mbus1.Preset("offsetX", 1, "RO", 9000, "float")
```

```
    while (true)
    {
        PathOffset_AlphaFilter(0.005)      // Set the alpha coeffcient
        PathOffset_MaxOffset(20, 5)        // Set the offset compensation upper bound

        // Read the required offset compensation value from mbus1.
        var_X = modbus_read("mbus1", "offsetX")

        var_Offset[0] = var_X              // Offset to the X coordinate.
        PathOffset_Set(var_Offset, 1)      // Update the offset value by the tool base.

        Sleep(10)
    }
}
```

13.27 Velocity()

Define and activate continuous speed control mode. Under this mode, robot will change motion instantaneously once the target speed vector changes.

* Syntax 1/2/3/4 is to define the motion parameters, while syntax 5/6, the target speed vector.
* When the robot is in continuous speed control mode, sending any other types of motion control commands (such as PTP(), Line(), etc.) will trigger an error stop.
* This function is not affected by the project override speed (%), and the robot will run at the speed specified in the function within the reachable speed range.
* Users must carefully assess the risk of the trajectory generated by Velocity() before sending the command. In other words, users or the motion control program must constantly check whether the robot is moving beyond its working range or nearing a singularity.

Syntax 1

```
bool Velocity(
    bool,
    string,
    int,
    int
)
```

Parameter

bool	whether to enable the adaptive speed control mode or not false disable true enable
string	control mode "C": linear speed control with the current base "T": linear speed control with the tool base "J": angular speed control with joint angles
int	The time interval to accelerate to top speed (ms). Valid range: 150 between 2000
int	The control value protection time (millisecond). Valid value >= 0. If users do not update and it is beyond the protection time, the Velocity(float[]) value will be adjusted to 0 automatically. * While disable can be called in the process or threads, enable must be called in the process.

Return

bool	True Command accepted; False Command rejected (format error)

Syntax 2

bool **Velocity**(
bool,
string,
int
)

Parameter

bool	whether to enable the adaptive speed control mode or not false disable true enable
string	control mode "C": linear speed control with the current base "T": linear speed control with the tool base "J": angular speed control with joint angles
int	The time interval to accelerate to top speed (ms). Valid range: 150 between 2000 * While disable can be called in the process or threads, enable must be called in the process.

Note

Same as syntax 1. It sets a 1000ms to the control value protection time.

Syntax 3

bool **Velocity**(
bool,
string
)

Parameter

bool	whether to enable the adaptive speed control mode or not false disable true enable
string	control mode "C": linear speed control with the current base "T": linear speed control with the tool base "J": angular speed control with joint angles * While disable can be called in the process or threads, enable must be called in the process.

Note

Same as syntax 1. It sets a 500 ms to the time interval to accelerate to the top speed and a 1000ms to the control value protection time.

Syntax 4

bool **Velocity**(
    bool
)

Parameter

bool		whether to enable the adaptive speed control mode or not
	false	disable
	true	enable

* Disable can be called in the process or threads.
* For disable only.

Note

If on the Flow page

Velocity(true, "C", 300, 3000)

// Enable velocity control for the linear speed by the current base, setting a 500 ms time interval to accelerate to the top speed and a 3000 ms control value protection time.

Velocity(true, "T", 300)

// If continuing from the previous line, the "C" control will be turned off first.

// Enable velocity control for the linear speed by the tool base, setting a 500 ms time interval to accelerate to the top speed and a 1000 ms control value protection time.

Velocity(true, "J")

// If continuing from the previous line, the "T" control will be turned off first.

// Enable velocity control for the angular speed by the joint angle, setting a 500 ms time interval to accelerate to the top speed and a 1000 ms control value protection time.

Position(true, "J")

If continuing from the previous line, the "T" control will be turned off first.

// Enable position control // Only one control, Position or Velocity, can be active at a time.

Velocity(false) // Disable velocity control

Velocity(true) // Return error. Control Mode Parameters Required to enable

If on the Thread page

Velocity(true, "J") // Return error. Must be in the Flow page to enable velocity control

Velocity(false) // Disable velocity control

Syntax 5

bool **Velocity**(
float[]
)

Parameter

float[]	Speed control value for the associated applicable control mode "C" or "T": linear speed control for X,Y,Z (mm/s) RX,RY,RZ (degree/s) "J": angular speed control for J1,J2,J3,J4,J5,J6 (degree/s)

* Calling available in the process or threads.

Return

bool	True Command accepted; False Command rejected

Syntax 6

bool **Velocity**(
float, float, float, float, float, float
)

Note

Same as syntax 5. It replaces float[] with parameters float,float,float,float,float,float.

```
PTP("JPP", {90,0,90,0,90,0}, 10, 500, 0, true)
Velocity(true, "J", 150, 5000)
// Enable adaptive speed control for the angular speed by the joint angle

Sleep(1000)
for (int i = 0; i < 30; i++)
{
    float[] AngleSpeed = {0, 0, i, 0, 0, 0} // Adjust the speed for angle J3 along with the loop.
    Velocity(AngleSpeed)                    // Set the speed for angle J30
    Sleep(100)
}
Velocity(false)
```

13.28 Position()

Define and activate continuous position control mode. Under this mode, the robot will change motion instantaneously once the target position vector changes.

* Syntax 1/2/3/4 is to define the motion parameters, while syntax 5/6, the target position vector.
* When the robot is in continuous position control mode, sending any other types of motion control commands (such as PTP(), Line(), etc.) will trigger an error stop.
* Users must carefully assess the risk of the trajectory generated by Position() before sending the command. In other words, users or the motion control program must constantly check whether the robot is moving beyond its working range or nearing a singularity.

Syntax 1

```
bool Position(
    bool,
    string,
    int,
    float,
    int
)
```

Parameter

bool	whether to enable the position adaptive speed control mode or not false disable true enable
string	control mode "C": target coordinate control with the current base "T": target coordinate control with the tool base "J": target angle control with the joint angle
int	The time interval to accelerate to top speed (ms). Valid range: 150 between 2000
float	The Motion Control Gain value. Valid range: 1 between 100. The larger the value, the faster the response to the new control value.
int	The expected control value protection time interval (millisecond). Valid value >= 20. In adaptive control mode, **Position**(float[]) requires updating regularly. If the difference from the expected time interval varies significantly (less or more than), it will affect the control speed algorithm. * While disable can be called in the process or threads, enable must be called in the process.

Return

bool	True Command accepted; False Command rejected (format error)

Syntax 2

```
bool Position(
    bool,
    string,
    int,
    float
```

)

Parameter

bool	whether to enable the position adaptive speed control mode or not false disable true enable
string	control mode "C": target coordinate control with the current base "T": target coordinate control with the tool base "J": target angle control with the joint angle
int	The time interval to accelerate to top speed (ms). Valid range: 150 between 2000
float	The Motion Control Gain value. Valid range: 1 between 100. The larger the value, the faster the response to the new control value. * While disable can be called in the process or threads, enable must be called in the process.

Note

Same as syntax 1. It sets a 1000ms to the expected control value protection time interval.

Syntax 3

bool **Position**(
bool,
string
)

Parameter

bool	whether to enable the position adaptive speed control mode or not false disable true enable
string	control mode "C": target coordinate control with the current base "T": target coordinate control with the tool base "J": target angle control with the joint angle * While disable can be called in the process or threads, enable must be called in the process.

Note

Same as syntax 1. It sets a 500 ms to the time interval to accelerate to the top speed, a 4.0 to the motion control gain value, and a 1000ms to the expected control value protection time.

Syntax 4

bool **Position**(
    bool
)

Parameter

bool	whether to enable the adaptive speed control mode or not	
	false	disable
	true	enable

* Disable can be called in the process or threads.
* For disable only.

Note

If on the Flow page

Position(true, "C", 300, 3, 500)

// Enable position control for the target coordinate control by the current base, setting a 300 ms to the time interval to accelerate to the top speed, a 3.0 to the motion control gain value, and a 500ms to the expected control value protection time.

Position(true, "T", 300, 3)

// If continuing from the previous line, the "C" control will be turned off first.

// Enable position control for the target coordinate control by the tool base, setting a 300 ms to the time interval to accelerate to the top speed, a 3.0 to the motion control gain value, and a 1000ms to the expected control value protection time.

Position(true, "J")

// If continuing from the previous line, the "T" control will be turned off first.

// Enable position control for the target angle control by the joint angle, setting a 500ms to the time interval to accelerate to the top speed, a 4.0 to the motion control gain value, and a 1000ms to the expected control value protection time.

Velocity(true, "J")

// If continuing from the previous line, the Position "J" control will be turned off first.

// Enable velocity control // Only one control, Position or Velocity, can be active at a time.

Position(false) // Disable position control

Position(true) // Return error. Control Mode Parameters Required to enable

If on the Thread page

Position(true, "J") // Return error. Must be in the Flow page to enable position control

Position(false) // Disable position control

Syntax 5

bool **Position**(
    float[]
)

Parameter

float[]	Position control value for the associated applicable control mode "C" or "T": target coordinate control for X,Y,Z (mm) RX,RY,RZ (degree) "J": target angle control for J1,J2,J3,J4,J5,J6 (degree)

* Calling available in the process or threads.

Return

bool	True Command accepted; False Command rejected

Syntax 6

bool **Position**(
    float, float, float, float, float, float
)

Note

Same as syntax 5. It replaces float[] with parameters float,float,float,float,float,float.

```
PTP("JPP", {90,0,90,0,90,0}, 10, 500, 0, true)
Position(true, "J", 150, 1, 500)        // Enable positon control by the angle
Sleep(1000)
for (int i = 0; i < 30; i++)
{
    float[] AngleTarget = {90, 0, 90+i, 0, 90, 0}
    // Adjust the angle for axix-angle J3 along with the loop.
    Position(AngleTarget)  // Set the speed for angle J30
    Sleep(100)
}
Position(false)
```

13.29 SetTCPSpeedLimit()

Set Linear Speed Limit and Rotation Speed Limit for Line Motion.

Syntax 1

bool **SetTCPSpeedLimit**(
bool,
int,
int
)

Parameter

bool	whether to enable the line motion speed limit	
	false	disable. Limited by the system default.
	true	enable. Limited by the input parameters for linear and rotation.
int	Linear speed limit, expressed as mm/s. Maximum limit if <= 0.	
int	Rotation speed limit, expressed as deg/s. Maximum limit if <= 0.	

Return

bool	True	Command accepted; False Command rejected.

Syntax 2

bool **SetTCPSpeedLimit**(
int,
int
)

Parameter

int	Linear speed limit, expressed as mm/s. Maximum limit if <= 0.
int	Rotation speed limit, expressed as deg/s. Maximum limit if <= 0.

Note

Same as syntax 1. It sets true to whether to enable the line motion speed limit.

Syntax 3

bool **SetTCPSpeedLimit**(
bool
)

Parameter

bool	whether to enable the line motion speed limit	
	false	disable. Limited by the system default.
	true	enable. Limited by the input parameters for linear and rotation.

Return

bool	True	Command accepted; False Command rejected.

Note

When activated, the line motion speed limit uses the existing settings for the Linear Speed Limit and the Rotation Speed Limit. It defaults the limits to the maximum if never set.

```
SetTCPSpeedLimit(true, 0, 0)
Display("Default Speed Limit")
Line("CPP",{517.67212,-331.18498,343.19177,179.75342,-
0.32395,89.91306},100,600,0,false)  // Point1
Line("CPP",{517.67505,-131.19205,343.19144,89.83959,89.9993,0},100,600,0,false)
```

```
        // Point2
Line("CPP",{517.67212,-331.18498,343.19177,179.75342,-
0.32395,89.91306},100,600,0,false)  // Point1

SetTCPSpeedLimit(true, 0, 30)
Display("Rotational Speed Limit = 30 deg/s")
Line("CPP",{517.67212,-331.18498,343.19177,179.75342,-
0.32395,89.91306},100,600,0,false)  // Point1
Line("CPP",{517.67505,-131.19205,343.19144,89.83959,89.9993,0},100,600,0,false)
        // Point2
Line("CPP",{517.67212,-331.18498,343.19177,179.75342,-
0.32395,89.91306},100,600,0,false)  // Point1

SetTCPSpeedLimit(false)          // Disable. Limited by the system default.
```

13.30 SetAccTable()

Set the acceleration table, and the system will automatically fetch the speed and the time to top speed from the table by the distance when the robot is in motion control. Currently, it is available for the TM Robot S series models.

The acceleration table comes with five groups at most and with some rules.

1. There must be two groups at least, and the first and the last group cannot be disabled.
2. The maximum distance of each group must be greater than or equal to the maximum distance of the previous group.
3. If Speed 2 (%) gets more than Speed 1 (%), it means speed up with distance; if less, it means speed down with distance.
4. The default values vary from the robot models. The table below exemplifies one of the default values in the acceleration table.

Distance Min (mm)	Distance Max (mm)	Speed 1 (%)	Speed 2 (%)	Time to Top Speed 1 (ms)	Time to Top Speed 2 (ms)
0	50	5	15	172.5	217.5
50	300	15	45	217.5	352.5
300	700	45	65	352.5	442.5
700	1000	65	75	442.5	487.5
1000	1300	75	100	487.5	600

Syntax 1

bool **SetAccTable**(
)

Parameter

void No input

Return

bool True Command accepted; False Command rejected.

Note

Reset the acceleration table to defaults.

Syntax 2

bool **SetAccTable**(
int,
float,
float,
float,
float
)

Parameter

int The acceleration table group. Valid from1 to 5.
float Distance Max (mm). A value of <= 0 means the group configuration is disabled. (Configuration disabling is available for intermediate groups.)
float Speed 1 (%)
float Speed 2 (%)
float Time to Top Speed 2 (ms)

Return

bool True Command accepted; False Command rejected.

Note

Time to top speed 1 (ms) is calculated using the following equation:

$$Time\ to\ Top\ Speed\ 1 = Accelerate\ Time\ Min + \frac{Speed\ 1\ \times (Time\ to\ Top\ Speed\ 2 - Accelerate\ \ Time\ Min)}{Speed\ 2}$$

* Where *Accelerate Time Min* is defined based on the robot model.

Syntax 3

bool **SetAccTable**(
    int,
    float,
    float,
    float
)

Parameter

int	The acceleration table group. Valid from1 to 5.
float	Distance Max (mm). A value of <= 0 means the group configuration is disabled. (Configuration disabling is available for intermediate groups.)
float	Speed 1 (%)
float	Speed 2 (%)

Note

Time to top speed 1 (ms) and Time to top speed 2 (ms) are calculated using the following equation:

$$Time\ to\ Top\ Speed\ 1 = Accelerate\ Time\ Min + \frac{Speed\ 1\ \times (Accelerate\ Time\ Default - Accelerate\ \ Time\ Min)}{100}$$

$$Time\ to\ Top\ Speed\ 2 = Accelerate\ Time\ Min + \frac{Speed\ 2\ \times (Accelerate\ Time\ Default - Accelerate\ \ Time\ Min)}{100}$$

* Where *Accelerate Time Min* and *Accelerate Time Default* are defined based on the robot model.

Syntax 4

bool **SetAccTable**(
    int,
    float,
    float
)

Parameter

int	The acceleration table group. Valid from1 to 5.
float	Distance Max (mm). A value of <= 0 means the group configuration is disabled. (Configuration disabling is available for intermediate groups.)
float	Speed 2 (%)

Note

Same as syntax 3. It sets Speed 1 (%) the same as Speed 2 (%).

Syntax 5

bool **SetAccTable**(
    int,

bool
)

Parameter

int	The acceleration table group. Valid from 2 to 4. Groups 1 and 5 are permanently enabled.
bool	Enable or disable the configuration of the group.

Return

bool	True	Command accepted; False Command rejected.

Note

The acceleration table requires at least two groups (groups 1 and 5), so the sequence of groups to be enabled or disabled is 2 to 4.

13.31 GetAccTable()

Retrieve the contents of the acceleration table. Available for TM Robot S series models currently.

Syntax 1

float[] **GetAccTable**(
    int
)

Parameter

int	The acceleration table group. Valid from1 to 5.

Return

float[]	Retrieve the setting of the acceleration table index associated group. The array length is six and goes by Distance Min, Distance Max, Speed 1, Speed 2, Time to Top Speed 1, and Time to Top Speed 2. If all the values in the array are 0, the group configuration is closed.

Note

```
SetAccTable()       // Reset the acceleration table to defaults.
string s1
for (int i = 1; i <= 5; i++)
        s1 += GetString(GetAccTable(i)) + newline
Display(s1)
// {0,50,5,15,172.5,217.5}\u0D0A
   {50,300,15,45,217.5,352.5}\u0D0A
   {300,700,45,65,352.5,442.5}\u0D0A
   {700,1000,65,75,442.5,487.5}\u0D0A
   {1000,1300,75,100,487.5,600}
Pause()

SetAccTable(1, 50, 10, 20, 220)
SetAccTable(2, 320, 20, 50)
SetAccTable(3, 750, 70)
SetAccTable(4, false)
SetAccTable(5, 1300, 100)
string s2
for (int i = 1; i <= 5; i++)
        s2 += GetString(GetAccTable(i)) + newline
Display(s2)
// {0,50,10,20,185,220}\u0D0A
   {50,320,20,50,240,375}\u0D0A
   {320,750,70,70,465,465}\u0D0A
   {0,0,0,0,0}\u0D0A
   {750,1300,100,100,600,600}
```

13.32 Vision_DoJob()

Execute the existing vision jobs in the project but not the ones with vision capture points.

* Must create vision jobs in the project first without checking **Vision Capture Point**.
* It is required to codify the respective variable definitions in the define segment if using script projects.
* The respective variable definition values update after the vision job execution.

Syntax 1

bool **Vision_DoJob**(
    string
)

Parameter

string		Vision job name.

Return

bool	True	Vision job completed and the result is pass.
	False	Vision job failed. 1. The result is fail. 2. Fail to execute. 3. Vision job comes with the initial point.

Note

bool var_result = **Vision_DoJob**("job1")

13.33 Vision_DoJob_PTP()

Execute the existing vision jobs in the project, move to the vision capture point by the PTP motion, and queue with the motion commands.

* Must create vision jobs in the project first. Check **Vision Capture Point** for moving to the initial position and uncheck for not.
* It is required to codify the respective variable definitions in the define segment if using script projects.
* The respective variable definition values update after the vision job execution.

Syntax 1

bool **Vision_DoJob_PTP**(
string,
int,
int,
bool
)

Parameters

string	Vision job name.
int	The robot end moving speed setting, expressed as a percentage (%) ≥0 Percentage of speed (%) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value
int	The time interval to accelerate to top speed (ms). Invalid when using the Acceleration Table.
bool	Whether to use the smart pose of robot selection mode true Use the pose of robot by the system. false Use the pose of robot recorded teaching the vision job.

Return

bool	True	Vision job completed and the result is pass.
	False	Vision job failed. 1. The result is fail. 2. Fail to execute.

Syntax 2

bool **Vision_DoJob_PTP**(
string,
int,
int
)

Note

Same as syntax 1. It defaults false to whether to use the smart pose of robot selection mode.

bool var_result = **Vision_DoJob_PTP**("job1", 100, 500)
var_result = **Vision_DoJob_PTP**("job1", 100, 500, true)

13.34 Vision_DoJob_Line()

Execute the existing vision jobs in the project, move to the initial position by the line motion, and queue with the motion commands.
*Must create vision jobs in the project first. Check **Start at Initial Position** for moving to the initial position and uncheck for not.
*It is required to codify the respective variable definitions in the define segment if using script projects.
* The respective variable definition values update after the vision job execution.

Syntax 1

bool **Vision_DoJob_Line**(
    string,
    int
)

Parameters

string	Vision job name	
int	The robot end moving speed setting, expressed as a percentage (%) ≥0 Percentage of speed (%) -1 Using the Acceleration Table (supported on TM Robot S series models) <0 Invalid value	

Return

bool	True	Vision job completed and the result is pass.
	False	Vision job failed. 1. The result is fail. 2. Fail to execute.

Note

bool var_result = **Vision_DoJob_Line**("job1", 100)

Syntax 2

bool **Vision_DoJob_Line**(
    string,
    int,
    int
    bool
)

Parameters

string	Vision job name	
int	The robot end moving speed setting, expressed as an absolute speed (mm/s)	
int	The time interval to accelerate to top speed (ms)	
bool	Whether to link to the project speed.	
	True	Link to the project speed.
	false	Unlink to the project speed.

Return

bool	True	Vision job completed and the result is pass.
	False	Vision job failed. 1. The result is fail.

2. Fail to execute.

Syntax 3

bool **Vision_DoJob_Line**(
    string,
    int,
    int
)

Note

Same as systax 2. It defaults true to whether to link to the project speed.

bool var_result = **Vision_DoJob_Line**("job1", 100, 500)
var_result = **Vision_DoJob_Line**("job1", 100, 500, false)

14. Vision Functions

14.1 Vision_IsJobAvailable()

Check if the vision job in the current project present and valid

Syntax 1

bool **Vision_IsJobAvailable**(
    string
)

Parameter

string	Vision job name	

Return

bool	True	the vision present and valid
	False	the vision absent and invalid

Note

Use this function to check the presence and validity of the visual job before calling to avoid errors caused by absence or invalidity while calling.

bool var_result = **Vision_IsJobAvailable**("job1")

14.2 Multi-Object Result Output and Flying Trigger/Inspection Tasks

Once the parameters in the output result of the vision job come with more than one dimensions, or the visual job is created by Flying Trigger/Inspection, it requires function calls for the relevant information retrieval. The parameter should lead in the variable name, which indicates the result data of the desired vision job and the module to retrieve. For example, “Job1_Count_Blob_1_DetectObjectX_TM” is the output variable of the vision job Job1, which is output by the Counting (Blobs) module 1. If there are multiple object outputs in the vision job, the output variable values of the Counting (Blobs) module will be a two-dimensional array. Each row of the array denotes the result of an object (find), and each column signifies the multiple results of that object.

14.2.1 Vision_GetOutputArraySize()

Retrieve the array size of the 2D output variables after the vision job execution.

- **For vision jobs not created by Flying Trigger or Flying Inspection.**

Syntax 1

int **Vision_GetOutputArraySize**(
    string
)

Parameter

string	The variable name as the output by the vision job

Return

int	the object count. (the row count of the 2D array)

Syntax 2

int **Vision_GetOutputArraySize**(
    string,
    int
)

Parameter

string	The variable name as the output by the vision job
int	the object index. (the row index of the 2D array)

Return

int	The length of the result array under the object. (row index).

- **For vision jobs created by Flying Trigger or Flying Inspection.**

Syntax 1

int **Vision_GetOutputArraySize**(
    string
    int or string
)

Parameter

string	The variable name as the output by the vision job
int or string	The index of the same visual job name or the name of the Flying point in in Flying Trigger/Inspection.

Return

int	the object count. (the row count of the 2D array)

Syntax 2

int **Vision_GetOutputArraySize**(
    string,
    int or string,
    int
)

Parameter

string	The variable name as the output by the vision job
int or string	The index of the same visual job name or the name of the Flying point in in Flying Trigger/Inspection.
int	the find object index. (the row index of the 2D array)

Return

int	The length of the result array under the object. (row index).

14.2.2 Vision_GetOutputArrayValue()

Retrieve the array values of the 2D output variables after the vision job execution.

- **For vision jobs not created by Flying Trigger or Flying Inspection.**

Syntax 1

string[] **Vision_GetOutputArrayValue**(
    string,
    int
)

Parameter

string	The variable name as the output by the vision job with the data type of string array.
int	the object index. (the row index of the 2D array)

Return

?[]	The result array under the object. (row index).

Syntax 2

string **Vision_GetOutputArrayValue**(
    string,
    int,
    int
)

Parameter

string	The variable name as the output by the vision job with the data type of string array.
int	the object index. (the row index of the 2D array)
int	The output result array value under the object. (column index)

Return

?[]	The result value of the column index in the result array under the object. (row index).

- **For vision jobs created by Flying Trigger or Flying Inspection.**

Syntax 1

? **Vision_GetOutputArrayValue**(
    string
    int or string
)

Parameter

string	The variable name as the output by the vision job
int or string	The index of the same visual job name or the name of the Flying point in in Flying Trigger/Inspection.

Return

?	The result output value

Syntax 2

? **Vision_GetOutputArrayValue**(
    string,
    int or string,
    int
)

Parameter

string	The variable name as the output by the vision job
int or string	The index of the same visual job name or the name of the Flying point in in Flying Trigger/Inspection.
int	The index value. It can be a result index in a single-object multi-result value or an object index in a multi-object single-result value.

Return

?	The result output value

Syntax 3

? **Vision_GetOutputArrayValue**(
string,
int or string,
int,
int
)

Parameter

string	The variable name as the output by the vision job
int or string	The index of the same visual job name or the name of the Flying point in in Flying Trigger/Inspection.
int	the object index. (the row index of the 2D array)
int	The output result array value under the object. (column index)

Return

?	The result value of the column index in the result array under the object. (row index).

- **For vision jobs not created by Flying Trigger or Flying Inspection.**

Suppose that the visual job Job1 has four objects (find). The Counting Blobs result of the first object is “0”, “1”, and “2”. The Counting Blobs result of the second object is “3” and “4”. The Counting Blobs result of the third object is “5”, and the Counting Blobs result of the fourth object is “6” and “7”. Then, the variable Job1_Count_Blob_1_DetectObjectX_TM represents the result as an array: { {"0", "1", "2"}, {"3", "4"}, {"5"}, {"6", "7"} }.

Row \ Column	0	1	2
0	"0"	"1"	"2"
1	"3"	"4"	
2	"5"		
3	"6"	"7"	

- *Get the object (find) count*

Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM")
// Retrieve the row count of the variable *Job1_Count_Blob_1_DetectObjectX_TM* (i.e. the object (find) count)
// 4 // Row count
Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 1)
// Retrieve the array length of the output result from row 1, the 2nd object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM*
// 2 // Column count of Row[1]

- *Get the object (find) result value*

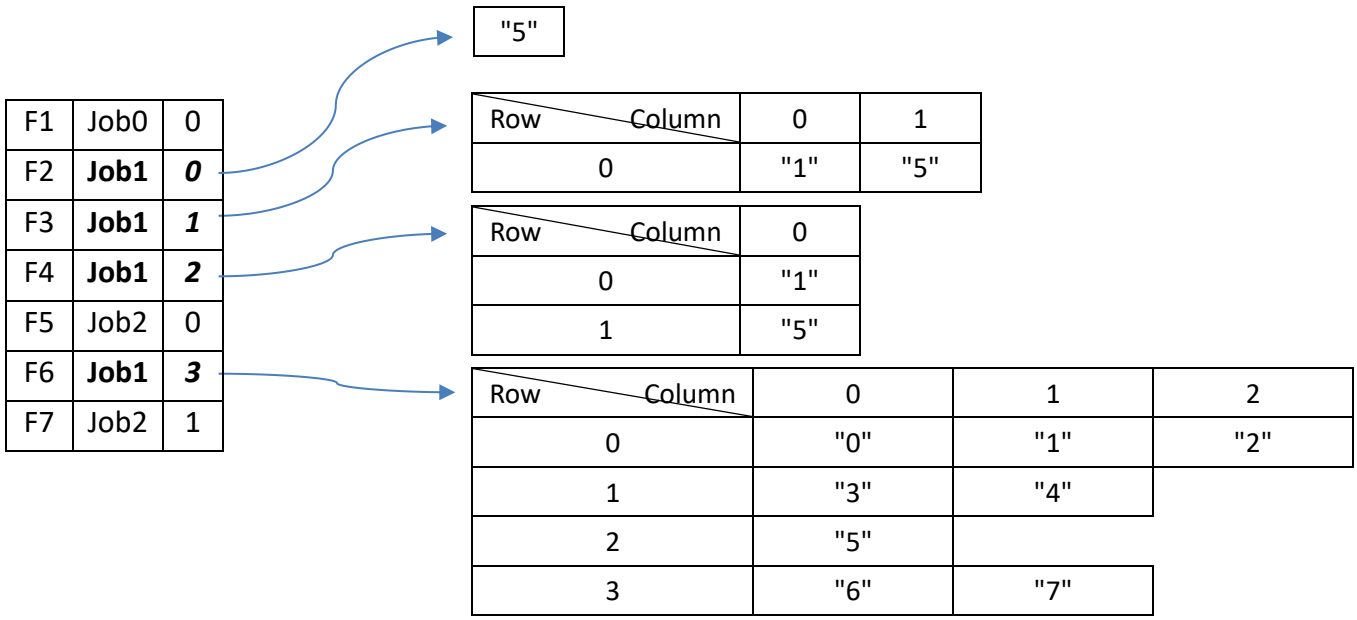
Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 0)
// Retrieve the array of the output result from row 0, the 1st object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM*

// {"0", "1", "2"}
Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 2, 0)
// Retrieve the output result from row 2 and column 0, the 3rd object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM*

```
// "5"
Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 4, 0)
// Return error. Exceeding the access range. (the object (find) count is 4, and the valid index is 0 to 3.
```

- **For vision jobs not created by Flying Trigger or Flying Inspection.**

In Flying Trigger or Flying Inspection, users can select the same vision job for repetitive execution. Therefore, the added parameter is the index or the flying point name that uses the same vision job name in Flying Trigger/Inspection. Assume the list of the vision job selected in Flying Trigger/Inspection is {“Job0”, “Job1”, “Job1”, “Job1”, “Job1”, “Job2”, “Job1”, “Job2”}, and assume the count of its output objects and the result value is as follows.0



F1	Job0	0
F2	**Job1**	***0***
F3	**Job1**	***1***
F4	**Job1**	***2***
F5	Job2	0
F6	**Job1**	***3***
F7	Job2	1

"5"

Row \ Column	0	1
0	"1"	"5"

Row \ Column	0
0	"1"
1	"5"

Row \ Column	0	1	2
0	"0"	"1"	"2"
1	"3"	"4"	
2	"5"		
3	"6"	"7"	

(1) Suppose the output of the first Job1 is a **single object and a single result value**.

F1	Job0	0
F2	**Job1**	***0***
F3	**Job1**	***1***
F4	**Job1**	***2***
F5	Job2	0
F6	**Job1**	***3***
F7	Job2	1



- *Get the object (find) count*

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 0)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F2")

  // Retrieve the row count (i.e. the object (find) count) of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the first Job1 (the flying point name is F2.)

  // 1 // Row count

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 0, 0)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F2", 0)

  // Retrieve the array length of the output result from row 0, the 1st object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the first Job1 (the flying point name is F2.)

  // 1 // Column count of Row[1]

- *Get the object (find) result value*

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 0)

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F2")

  // Retrieve the output result of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the first Job1 (the flying point name is F2.)

  // "5"

(2) Suppose the output of the second Job1 is a **single object and a multiple result value**.

F1	Job0	0
F2	**Job1**	***0***
F3	**Job1**	***1***
F4	**Job1**	***2***
F5	Job2	0
F6	**Job1**	***3***
F7	Job2	1

Row \ Column	0	1
0	"1"	"5"

- *Get the object (find) count*

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 1)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F3")

  // Retrieve the row count (i.e. the object (find) count) of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the second Job1 (the flying point name is F3.)

  // 1 // Row count

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 1, 0)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F3", 0)

  // Retrieve the array length of the output result from row 0, the 1st object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the second Job1 (the flying point name is F3.)

  // 2 // Column count of Row[1]

- *Get the object (find) result value*

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 1, 0)

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F3",0)

  // Retrieve the index 0 output result of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the second Job1 (the flying point name is F3.)

  // "1"

(3) Suppose the output of the third Job1 is a multiple object and a single result value.

F1	Job0	0
F2	**Job1**	***0***
F3	**Job1**	***1***
F4	**Job1**	***2***
F5	Job2	0
F6	**Job1**	***3***
F7	Job2	1



Row \ Column	0
0	"1"
1	"5"

- *Get the object (find) count*

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 2)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F4")

  // Retrieve the row count (i.e. the object (find) count) of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the third Job1 (the flying point name is F4.)

  // 2 // Row count

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 2, 1)

  Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F4", 1)

  // Retrieve the array length of the output result from row 1, the 2nd object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the third Job1 (the flying point name is F4.)

  // 1 // Column count of Row[1]

- *Get the object (find) result value*

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 2, 1)

  Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F4",1)

  // Retrieve the index 1 output result of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the third Job1 (the flying point name is F4.)

  // "5"

(4) Suppose the output of the fourth Job1 is a multiple object and a multiple result value.

F1	Job0	0
F2	**Job1**	***0***
F3	**Job1**	***1***
F4	**Job1**	***2***
F5	Job2	0
F6	**Job1**	***3***
F7	Job2	1

Row \ Column	0	1	2
0	"0"	"1"	"2"
1	"3"	"4"	
2	"5"		
3	"6"	"7"	

- *Get the object (find) count*

Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 3)

Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F6")

// Retrieve the row count (i.e. the object (find) count) of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the fourth Job1 (the flying point name is F6.)

// 4 // Row count

Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", 3, 1)

Vision_GetOutputArraySize("Job1_Count_Blob_1_DetectObjectX_TM", "F6", 1)

// Retrieve the array length of the output result from row 1, the 2nd object, of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the fourth Job1 (the flying point name is F6.)

// 2 // Column count of Row[1]

- *Get the object (find) result value*

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 3, 0, 2)

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F6", 0, 2)

// Retrieve the output result in row 0, the 1st object, and column 2, item 3, of the variable *Job1_Count_Blob_1_DetectObjectX_TM* in the fourth Job1 (the flying point name is F4.)

// "2"

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 3, 4, 0)

// Return error. Exceeding the access range. (the object (find) count is 4, and the valid index is 0 to 3.)

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", 4, 0, 0)

// Return error. Exceeding the access range. (Job1 repeats four times, and the valid index is 0 to 3.)

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F8", 0, 0)

// Return error. The Flying point named “F8” does not exist.

Vision_GetOutputArrayValue("Job1_Count_Blob_1_DetectObjectX_TM", "F7", 0, 0)

// Return error. The vision job associated to the Flying point named “F7” is Job2

14.3 Vision_GetTriggerJobOutputCount()

Retrieve the output variable count in the buffer after the vision IO Trigger Job execution.

Syntax 1

int **Vision_GetTriggerJobOutputCount**(
    string
)

Parameter

string	The variable name as output by the IO Trigger Job with the data type of string array.

Return

int	The output variable count of the designated variable in the buffer.

14.4 Vision_GetTriggerJobOutputValue()

Retrieve the output variable values after the vision IO Trigger Job execution.. (Retrieve and remove from the buffer.)

Syntax 1

string[] **Vision_GetTriggerJobOutputValue**(
    string
)

Parameter

string	The variable name as output by the IO Trigger Job with the data type of string array.

Return

string[]	The output values of the designated variables in the buffer.

Note

After the vision IO Trigger Job execution (Enabling the IO trigger mode is a must during vision editing.), the result updates to the variable after each IO trigger. Since the output of the IO Trigger Job is multiple outputs, to prevent the output data from being overwritten because of out-of-process, it stores the output data in the buffer one by one (first in, first out), and users can use the function calls to retrieve the count or the values in the buffer. For example, job1_Count_Blob_1_DetectObjectX_TM is an output variable of the vision job job1 to be output by the Counting (Blobs) module 1. After the vision execution, it updates and stores the result in the buffer at each IO trigger, so users can call the functions to retrieve the count or the values of the variable job1_Count_Blob_1_DetectObjectX_TM in the buffer.

The buffer comes with a capacity limit. When results are about to enter, if the buffer capacity is insufficient, it removes the oldest data automatically and adds the latest to the buffer.

Suppose the current content in the buffer goes by { {"0", "1", "2"}, {"3", "4"}, {"5"} }

Retrieve the output variable count of the vision trigger job in the buffer.

```
int var_count = Vision_GetTriggerJobOutputCount
("job1_Count_Blob_1_DetectObjectX_TM")
  // var_count = 3
```

Retrieve the output variable values in the buffer.

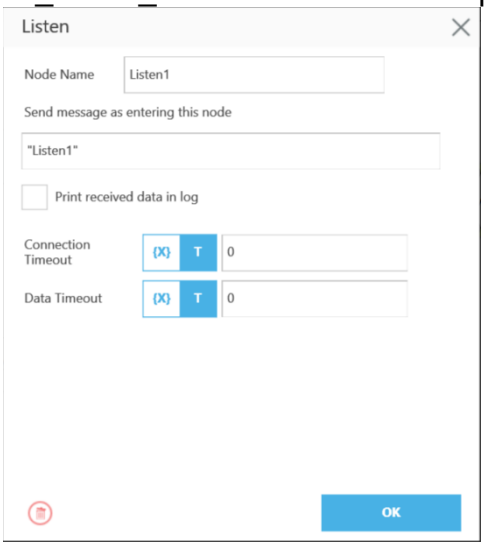
```
string[] var_s = Vision_GetTriggerJobOutputValue
("job1_Count_Blob_1_DetectObjectX_TM")
  // var_s = {"0", "1", "2"}
  // After retrieving, the content in the buffer turns to { {"3","4"}, {"5"} }.
var_count = Vision_GetTriggerJobOutputCount
("job1_Count_Blob_1_DetectObjectX_TM")
  // var_count = 2
var_s = Vision_GetTriggerJobOutputValue ("job1_Count_Blob_1_DetectObjectX_TM")
  // var_s = {"3","4"}
  // After retrieving, the content in the buffer turns to { {"5"} }.
var_s = Vision_GetTriggerJobOutputValue ("job1_Count_Blob_1_DetectObjectX_TM")
  // var_s = {"5"}
```

```
  // After retrieving, the content in the buffer turns to { }.
var_s = Vision_GetTriggerJobOutputValue ("job1_Count_Blob_1_DetectObjectX_TM")
  // var_s = {}
var_count = Vision_GetTriggerJobOutputCount
("job1_Count_Blob_1_DetectObjectX_TM")
  // var_count = 0
```

15. External Script

15.1 Listen Node

Users can establish a socket TCPlistener (server site) in the listen node to connect to external devices and communicate based on the packet format. All features available in TM_Robot_Function can also be operated in the listen node.



1. **Send Message:** When entering this node, it will initiate a message
2. **Print Log:** Enable Communication Log (shown on the right)
3. **Connection Timeout:** When entering this node, if more than the time (milliseconds) is not connected, it will be overtime.
   If <= 0, no timeout
4. **Data Timeout:** When connected, the timeout will be exceeded when there is no communication packet
   If <= 0, no timeout

Socket TCPListener is started up after the project being executed, and closed as the project stopped. The IP and listen port will be shown on the Notice Log window on the right, after the Socket TCPListener is started up.

IP HMI → System → Network → IP Address
Port 5890

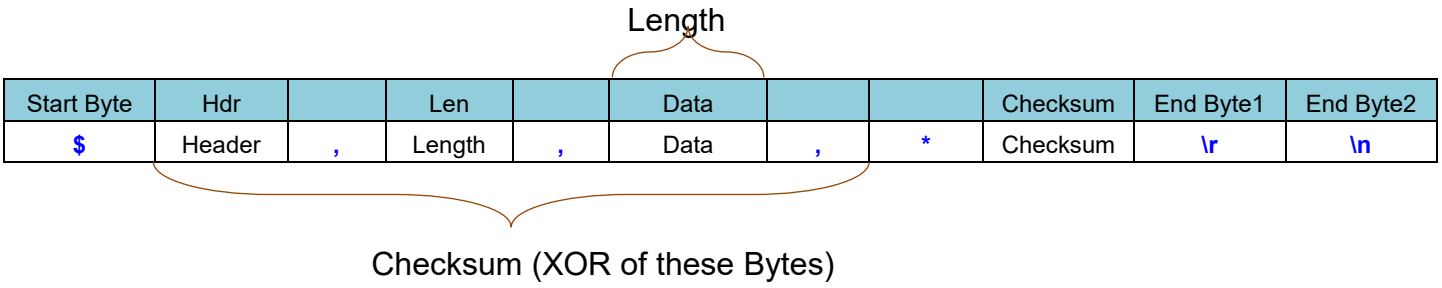
When entering the Listen Node, the flow will keep at Listen Node until either of the two exit conditions is fulfilled.

Pass: *ScriptExit()* is executed or the project is stopped
Fail: 1. Connection Timeout
2. Data Timeout
3. Before the TCP Listener is started up, the flow has entered this Listen Node

The command received by listen node will be executed in order. If the command is not valid, an error message will be returned carrying the line number with errors. If the command is valid, it will be executed.

The command can be divided into two categories. The first category is commands which can be accomplished in instance, like assigning variable value. The second category is commands needs to be executed in sequence, like motion command and IO value assigning. The second category command will be placed in queue and executed in order.

15.2 Communication Protocol



Name	Size	ASCII	HEX	Description
Start Byte	1	$	0x24	Start Byte for Communication
Header	*X*			Header for Communication
Separator	1	,	0x2C	Separator between Header and Length
Length	*Y*			Length of Data
Separator	1	,	0x2C	Separator between Length and Data
Data	*Z*			Communication Data
Separator	1	,	0x2C	Separator between Data and Checksum
Sign	1	*	0x2A	Begin Sign of Checksum
Checksum	*2*			Checksum of Communication
End Byte 1	1	\r	0x0D	
End Byte 2	1	\n	0x0A	End Byte of Communication

1. ***Header***
   Defines the purpose of the communication package. The data definition could be different with different Header.
   - *TMSCT* External Script
   - *TMSTA* Acquiring status or properties
   - *CPERR* Communication data error (E.g. Packet error, checksum error, header error, etc.)

2. ***Length***
   Length defines the length in UTF8 byte. It can be represented in decimal, hexadecimal or binary, the upper limit is int 32bits
   Example:

```
$TMSCT,100,Data,*CS\r\n      // Decimal 100, that is the data length is 100 bytes
$TMSCT,0x100,Data,*CS\r\n    // Hexadecimal 0x100, that is the data length is 256 bytes
$TMSCT,0b100,Data,*CS\r\n    // Binary 0b100, that is the data length is 4 bytes
$TMSCT,8,1,達明,*58\r\n      // The Data length  1,達明  is 8 bytes (UTF8)
```

3. ***Data***
   The content of the communication package. Arbitrary characters are supported (including 0x00 .. 0xFF in UTF8). The data length is defined in Length and the purpose is defined in Header

4. ***Checksum***
   The checksum of the communication package. The checksum is calculated with XOR(exclusive OR), and the range for checksum computation starts from $ to * ($ and * are

excluded) as shown below:

$TMSCT,100,Data,*CS\r\n

Checksum = Byte[1] ^ Byte[2] … ^ Byte[N-6]

The representation of checksum is fixed to 2 bytes in hexadecimal format (without 0x).

For example:

$TMSCT,5,10,OK,*6D

CS = 0x54 ^ 0x4D ^ 0x53 ^ 0x43 ^ 0x54 ^ 0x2C ^ 0x35 ^ 0x2C ^ 0x31 ^ 0x30 ^ 0x2C ^ 0x4F ^ 0x4B ^ 0x2C = 0x6D

CS = 6D (0x36 0x44)

15.3 TMSCT

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*TMSCT*	,	Length	,	Data	,	*	Checksum	\r	\n

ID		SCRIPT
Script ID	,	Script Language

TMSCT defines the communication package as External Script Language. In External Script Language, the data contains two parts and is separated by comma. One is ID and the other is SCRIPT

ID Script ID, can be arbitrary English character or number (a CPERR 04 error will be reported when encountering non-alphanumeric byte). The ID is used as specifying the target SCRIPT of return message.

, Separator

SCRIPT The content defined in Script Language. In a communication package, multi-line scripts can fit into the SCRIPT section with separator (0x0D 0x0A)

Note

TMSCT is available only when in the external script control mode, otherwise CPEER error packets will be replied.

Return (Robot→External Device)

1. When it enters Listen Node, the robot will send a message to all the connected device. The ID is set to 0.

   $***TMSCT***,9,0,Listen1,*4C\r\n

   9 The length of *0,Listen1* is 9 bytes

   0 The Script ID is 0

   , Separator

   Listen1 The message to send

2. The OK or ERROR message is replied according to the Script's content. For message with ;N, ;N represents the number of line with error or warning. After the message is received, robot will execute the message, then send back the return message, if the Script is valid. For invalid Script, the return message will be sent back immediately without executed.

   $***TMSCT***,4,1,OK,*5C\r\n // Response to ID 1

   // OK means valid Script.

   $***TMSCT***,8,2,OK;2;3,*52\r\n // Response to ID 2

   // OK;2;3 means valid Script with warnings in line 2 and 3.

   $***TMSCT***,13,3,ERROR;1;2;3,*3F\r\n // Response to ID 3

   // ERROR;1;2;3 means invalid Script with errors in line 1, 2 and 3.

Receive (Robot←External Device)

1. When it enters the listen node, the robot will start to receive, check, and execute the external script. If the robot did not enter the listen node (not in the external script control mode), the Script received will be disposed and CPEER error packets will be replied.
2. The message from external device should define the Script ID as a ID used in messages replied by robot.

   < $***TMSCT***,25,1,ChangeBase("RobotBase"),*08\r\n // Defined as ID 1

```
>  $TMSCT,4,1,OK,*5C\r\n                    // Response to ID 1
```

3. In a communication package, multi-line scripts can fit into the SCRIPT section with separator \r\n

```
<  $TMSCT, 72,2,ChangeBase("RobotBase")\r\n
   ChangeTCP("RobotEndFlange")\r\n
   ChangeLoad(10.1),* 5A\r\n
   // Three lines Script in a communication package (Lines are separated by \r\n)
>  $TMSCT,4,2,OK,*5F\r\n
```

4. In Listen Node, local variables are supported and valid before quitting the Listen Node.

```
<  $TMSCT,40,3,int var_i = 100\r\n
   var_i = 1000\r\n
   var_i++,*5A\r\n
>  $TMSCT,4,3,OK,*5E\r\n

<  $TMSCT,42,4,int var_i = 100\r\n
   var_i = 1000\r\n
   var_i++\r\n
   ,*58\r\n
>  $TMSCT,9,4,ERROR;1,*02\r\n
   // Because int var_i has been declared, an error occurred.
```

5. In the listen node, it is possible to access or modify the project's variables, but no new variable can be declared since the variables created in the listen node are local variables.

15.4 TMSTA

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*TMSTA*	,	Length	,	Data	,	*	Checksum	\r	\n

SubCmd		
SubCmd	…	…

(Based on SubCmd)

TMSTA defines the communication package as acquiring status or properties. The data section of the package contains different sub command (SubCmd). The package format could be different according to different SubCmd. The definitions are listed below.

SubCmd

00 In external script control mode or not

01 Complete the configured QueueTag numbering or not

90..99 Date message to send (the format of data is self-definable)

Note

TMSTA could be executed without entering the Listen Node

SubCmd 00 In external script control mode or not

Format

Response (Robot→External Device)

SubCmd		Entry		Message
00	,	false	,	
00	,	true	,	message

Receive (Robot←External Device)

SubCmd
00

Response (Robot→External Device)

1. If not in external script control mode, it will reply false.

   $***TMSTA***,9,00,false,,*37\r\n

   9 Indicates the length of 00,false, is 9 bytes

   00 Indicates SubCmd as 00

   , Separator

   false The flow has not entered Listen Node

   , Separator

   Empty string (Have not entered Listen Node)

2. If in external script control mode, it will reply true.

   $***TMSTA***,15,00,true,Listen1,*79\r\n

   15 Indicates the length of 00,true,Listen1 is 15 bytes

   00 Indicates SubCmd as 00

   , Separator

   true The flow has entered the Listen Node

   , Separator

   Listen1 The message to be sent as in Listen Node (It indicates the flow is in Listen1)

Receive (Robot←External Device)

1. Send to the robot from the external device
   $***TMSTA***,2,00,*41\r\n
   2 Indicates the length of 00 is 2 bytes.
   00 Indicates the SubCmd is 00 whether in external script control mode or not.

SubCmd ***01*** Complete the configured QueueTag numbering or not

Format

Send (Robot→External Device)

SubCmd		Tag Number		Status
01	,	01 .. 15	,	true/false/none

Receive (Robot←External Device)

SubCmd		Tag Number
01	,	01 .. 15

Note

When inquiring with TMSTA 01, users can look up to the status of the last 4 tag numbers.

Send (Robot→External Device)

1. Send to the external device from the robot. Spontaneously sending after QueueTag numbering completed.
   $***TMSTA***,10,01,08,true,*6D\r\n
   10 Indicates the length of 01,00,true is 10 bytes
   01 Indicates SubCmd as 01 to send the status of Tag Number
   , Separation symbol
   08 Tag Number 08
   , Separation symbol
   true *true* Indicates Tag Number complete
   false Indicates Tag Number incomplete
   none Indicates Tag Number not existed

Receive (Robot←External Device)

1. Send from the external device to the robot. Users can look up to the status of the last 4 tag numbers.
   $***TMSTA***,5,01,15,*6F\r\n
   5 Indicates the length of 01,88 is 5 bytes
   01 Indicates SubCmd as 01 to send the status of Tag Number
   , Separation symbol
   15 Tag Number 15
   > $***TMSTA***,10,01,15,none,*7D\r\n // TagNumber 15 not existed
2. Tag Number uses the value of integers between 1 and 15. If the value is invalid, it relies none for not existed.
   $***TMSTA***,5,01,88,*6B\r\n
   > $***TMSTA***,10,01,88,none,*79\r\n // TagNumber 88 not existed

SubCmd ***90 .. 99*** Send data message

Format

Send (Robot→External Device)

SubCmd		Data
90 .. 99	,	…

Receive (Robot←External Device)

None

Note

1. When sending with TMSTA 90 .. 99, users can use their self-defined formats.
2. Self-defined formats denote the formats are defined by both the project flow and the external device.
3. To enhance the flexibility of usages, users can various SubCmd of 90 .. 99 to define different formats to send such as

   SubCmd 90 defined as string；
   SubCmd 91 defined as float[]；
   SubCmd 92 defined as byte[]
   …

   and so on for the external device to analyze and resolve based on the SubCmd with different methods.

Send (Robot→External Device)

1. Send to the external device from the robot. When the external script executes the ListenSend() function, it will send data.

```
string var_s = "Hello World"
float[] var_f = {1,2,3,4}
byte[] var_b = {0x10, 0x11, 0x12, 0x13}
ListenSend(90, var_s)
// the content of communication  $TMSTA,14,90,Hello World,*73\r\n
// 0x39,0x30,0x2C,0x48,0x65,0x6C,0x6C,0x6F,0x20,0x57,0x6F,0x72,0x6C,0x64
ListenSend(91, var_f)
// the content of communication  $TMSTA,19,91,…,*60\r\n
//
0x39,0x31,0x2C,0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40,0x00,0x00,0x80,0
x40
ListenSend(92, var_b)
// the content of communication  $TMSTA,7,92,…,*63\r\n
// 0x39,0x32,0x2C,0x10,0x11,0x12,0x13
```

15.5 CPERR

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*CPERR*	,	Length	,	Data	,	*	Checksum	\r	\n

Error Code
Code (00 .. FF)

CPERR defines the communication package as sending the Communication Protocol Error. The data section is defined as Error Code.

Error Code Error code, presented in 2 bytes hexadecimal format (without 0x)

- 00 Packet correct. No error. (The return message usually reply to the content of packet instead of returning no error)
- 01 Packet Error.
- 02 Checksum Error.
- 03 Header Error.
- 04 Packet Data Error.
- F1 Have not entered Listen Node

Note

Used by robot to response to external device

Response (Robot→External Device)

01 Packet Error

< $***TMSCT***,**-100**,1,ChangeBase("RobotBase"),*13\r\n // Length cannot be negative
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

01 Packet Error

< $***TMSCT***,**24**,1,ChangeBase("RobotBase"),*09\r\n
// Length value is incorrect (should be 25)
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

01 Packet Error

< $***TMSCT***,**26**,1,ChangeBase("RobotBase"),*0B\r\n
// When sending only the packet mentioned above, it will not bring out a response because its Length of 26 exceeds the actual data amount, indicating an insufficient number of packets.
< $***TMSCT***,**26**,1,ChangeBase("RobotBase"),*0B\r\n
// Length value is incorrect (should be 25)
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

01 Packet Error

< $***TMSCT***,25,1,ChangeBase("RobotBase"),***088**\r\n
// 088 is not a correct packet ending format.
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

01 Packet Error

< $***TMSCT***,25,1,ChangeBase("RobotBase"),***8**\r\n
// When sending only the packet mentioned above, it will not bring out a response because of a Checksum Byte coming short.

< $***TMSCT***,25,1,ChangeBase("RobotBase"),*8\r\n
// 8 is not a correct packet ending format.
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

01 Packet Error

< $***TMSCT***,25,1,ChangeBase("RobotBase"),*08\n
// When sending only the packet mentioned above, it will not bring out a response because of an End short.
< $***TMSCT***,25,1,ChangeBase("RobotBase"),*08\n
// \n is not a correct packet ending format.
> $***CPERR***,2,01,*49\r\n // CPERR Error Code 01

02 Checksum Error

< $***TMSCT***,25,1,ChangeBase("RobotBase"),*09\r\n // 09 is not a correct Checksum
> $***CPERR***,2,02,*4A\r\n // CPERR Error Code 02

03 Header Error

< $***TMsct***,25,1,ChangeBase("RobotBase"),*28\r\n // TMsct is not a correct Header
> $***CPERR***,2,03,*4B\r\n // CPERR Error Code 03

04 Packet Data Error

< $***TMSTA***,4,XXXX,*47\r\n // There is no XXXX SubCmd under TMSTA
> $***CPERR***,2,04,*4C\r\n // CPERR Error Code 04

F1 No External Script Mode

< $***TMSCT***,25,1,ChangeBase("RobotBase"),*0D\r\n
// Suppose currently not in external script control mode
> $***CPERR***,2,F1,*3F\r\n // CPERR Error Code F1

15.6 ScriptListen()

Enter the external script control mode.

Syntax 1

bool **ScriptListen**(
    string,
    bool,
    int,
    int
)

Parameters

string	The message string to send while in the external script control mode.
bool	Whether to display the receiving external messages in the notice window.
int	After entering external Script control mode, it will time out if not connected within a specific timeframe (measured in milliseconds). If <= 0 No timeout
Int	After entering external Script control mode and connected, it will time out if no communication packets received within a specific timeframe (measured in milliseconds). If <= 0 No timeout

Return

bool	When entering the external Script control mode, it will remain there until meeting certain conditions and exit by the conditions. True execute *ScriptExit()* or stop the project False 1. Connection Timeout occured 2. Data Timeout occured 3. If the TCP Listener fails to set up, ScriptListen() is invoked.

* Accessible only through the Listen node, the Script node, or Script project programming.

* Calling in the flow required.

Syntax 2

bool **ScriptListen**(
    string,
    bool
)

Note

Same as Syntax 1. Set the message strings to send and whether to show in the notice window. There is no timeout by default.

Syntax 3

bool **ScriptListen**(
    string
)

Note

Same as Syntax 1. Set the message strings to send. There is no show in the notice window and no timeout by default.

```
if (ScriptListen("Listen1", false, 0, 0))
    Display("PASS")
else
    Display("FAIL")
```

15.7 ScriptExit()

Exit the external script control mode.

Syntax 1

bool **ScriptExit**(
)

Parameters

void No parameter

Return

bool True Command accepted; False Command rejected (format error)

Note

Exit the external script control mode and wait for the command to finish, and then quit the listen node and move on with the pass route, or quit ScriptListen() and return True.

* Execute via TMSCT communication packets required.
* Functions after ScriptExit() will not be executed such as

```
<   $TMSCT,86,2,ChangeBase("RobotBase")\r\n
    ChangeTCP("RobotEndFlange")\r\n
    ScriptExit()\r\n                    // Exit the external script control mode.
    ChangeLoad(10.1),*58\r\n            // ChangeLoad will not be executed.
```

* After exiting the script mode, it is required to wait for all the commands and the functions to complete executions until quitting the listen node and moving on with the pass route. At the time being of waiting for quitting the listen node, it is not in the external script control mode, so no more external commands will be accepted and CPEER error packets will be replied.

15.8 Priority Commands

Due to the serial execution nature of the TMscript syntax, if using the queue syntax such as QueueTag(1, 1) or WaitQueueTag(1) to wait for the tag number to arrive, the program will stay put until the conditions are comprehended before going on execution. Therefore, if received the ScriptExit() syntax sent from the outside while waiting, it is impossible to exit the external Script control mode since the program is still waiting for the condition to meet.

When the program comes to the Listen node (the external Script control mode), other than the serial execution TMscript syntax, there are also priority commands to use. In Listen nodes, the priority commands go with a higher execution priority than the syntax execution, and the priority commands will run at once as defined below.

1. ***ScriptExit(0)***
   Stop the robot motion immediately, clear the robot motion instructions in the buffer, and exit the external Script control mode. Go to the Fail path after leaving the Listen node.

2. ***ScriptExit(1)***
   Stop the robot motion immediately, clear the robot motion instructions in the buffer, and exit the external Script control mode. Go to the Pass path after leaving the Listen node.

3. ***StopAndClearBuffer(0)***
   Stop the robot motion immediately and clear the robot motion instructions in the buffer.

4. ***StopAndClearBuffer(1)***
   Stop the robot motion immediately, clear the robot motion instructions in the buffer, exit the current Script program in execution, and continue to the next Script program.

5. ***StopAndClearBuffer(2)***
   Stop the robot motion immediately, clear the robot motion instructions in the buffer, exit the current Script program in execution, and clear all the script programs in the Received Script buffer.

- Priority commands support the general use of the command definitions only but not the use with variables and functions such as

```
<  $TMSCT,42,1,int var_st=2\r\n
   StopAndClearBuffer(var_st),*3A\r\n
>  $TMSCT,9,1,ERROR;2,*04\r\n        // Invalid syntax StopAndClearBuffer(var_st)
```

- Using priority commands with TMscript syntax leads to priority command executions only but not syntax executions.

```
<  $TMSCT,94,2,float[] targetP1= {0,0,90,0,90,0}\r\n // Will not execute.
   PTP("JPP",targetP1,10,200,0,false)\r\n            // Will not execute.
   StopAndClearBuffer(0),*75\r\n                     // Priority execution StopAndClearBuffer(0)
>  $TMSCT,4,2,OK,*5F\r\n
```

- The system will handle one priority command only in one external Script packet. If the packet comes with numerous priority commands, the system will handle ScriptExit(0/1) before StopAndClearBuffer(0/1/2). If there are numerous ScriptExit and

StopAndClearBuffer respectively, the system will handle the first only.

< $***TMSCT***,46,3,StopAndClearBuffer(2)\r\n // Will execute.
// There are many of StopAndClearBuffer and the system will handle the 1st of them.
StopAndClearBuffer(1),*68\r\n // Will not execute.
> $***TMSCT***,4,3,OK,*5E\r\n
< $***TMSCT***,61,4,StopAndClearBuffer(2)\r\n // Will not execute.
StopAndClearBuffer(1)\r\n // Will not execute.
ScriptExit(1),*52\r\n // Will execute.
// Due to the higher priority, the system handles ScriptExit before S topAndClearBuffer.
> $***TMSCT***,4,4,OK,*59\r\n

1. < $***TMSCT***,86,1,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1,1),*60\r\n // QueueTag(1,1) waits.
The program will stay put with the command until tag 1 finishes.
< $***TMSCT***,15,2,ScriptExit(0),*55\r\n
// When receiving the command ScriptExit(0), if tag 1 does not finish,
> $***TMSCT***,4,1,OK,*5C\r\n // Respond 1 OK
// It does not send out TMSTA tag number for finishing due to the clearing of the motion command and QueueTag().
> $***TMSCT***,4,2,OK,*5F\r\n // Respond 2 OK

It will exit the external Script control mode and go to the Fail path after leaving the Listen node.

2. < $***TMSCT***,86,1,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1,1),*60\r\n // QueueTag(1,1) waits.
The program will stay put with the command until tag 1 finishes.
< $***TMSCT***,23,2,StopAndClearBuffer(0),*55\r\n
// When receiving the command StopAndClearBuffer(0), if tag 1 does not finish
> $***TMSCT***,4,1,OK,*5C\r\n // Respond 1 OK
// It does not send out TMSTA tag number for finishing due to the clearing of the motion command and QueueTag().
> $***TMSCT***,4,2,OK,*5F\r\n // Respond 2 OK

It does not exit the external Script control mode and is still in the Listen node.

3. < $***TMSCT***,145,1,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1,0)\r\n
WaitQueueTag(0,60000)\r\n // Tag 0 will wait for the 60-seconds timeout.
PTP("JPP",targetP1,40,200,0,false),*64\r\n // It takes a 60-seconds wait before the execution.
< $***TMSCT***,23,2,StopAndClearBuffer(0),*55\r\n
// If receiving the command StopAndClearBuffer(0) in 60 seconds, it will clear the 1st PTP() function.
> $***TMSCT***,4,2,OK,*5F\r\n // Respond 2 OK

It waits for the 60-seconds timeout before the 2nd PTP() function execution and responds 1

OK.

> $***TMSCT***,4,1,OK,*5C\r\n // Respond 1 OK

* StopAndClearBuffer(0) clears the motion commands only but not the function syntax or the logic operations. While WaitQueueTag(0) sets the number 0, it waits for the timeout and is impossible to exit with the motion command clearing. It is required to use the command StopAndClearBuffer(1/2) to exit from the current Script program in execution.

4. < $***TMSCT***,86,1,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1,1),*60\r\n // QueueTag(1,1) waits.
The program will stay put with the command until tag 1 finishes.

< $***TMSCT***,86,2,float[] targetP2= {90,0,0,90,0,0}\r\n
PTP("JPP",targetP2,10,200,0,false)\r\n
QueueTag(2,1),*60\r\n // The last packet still waits, and this packet does not execute.

< $***TMSCT***,23,3,StopAndClearBuffer(1),*55\r\n
// When receiving the command StopAndClearBuffer(1), if tag 1 does not finish

> $***TMSCT***,4,1,OK,*5C\r\n // Respond 1 OK
// It does not send out TMSTA tag number for finishing due to the clearing of the motion command and QueueTag().

> $***TMSCT***,4,3,OK,*5E\r\n // Respond 3 OK

It clears and exits the current Script 1 in execution, and it continues to the next, Script 2.

> $***TMSCT***,4,2,OK,*5F\r\n // Respond 2 OK

> $***TMSTA***,10,01,02,true,*67\r\n // Tag 2 finished

5. < $***TMSCT***,86,1,float[] targetP1= {0,0,90,0,90,0}\r\n
PTP("JPP",targetP1,10,200,0,false)\r\n
QueueTag(1,1),*60\r\n // QueueTag(1,1) waits.
The program will stay put with the command until tag 1 finishes.

< $***TMSCT***,86,2,float[] targetP2= {90,0,0,90,0,0}\r\n
PTP("JPP",targetP2,10,200,0,false)\r\n
QueueTag(2,1),*60\r\n // The last packet still waits, and this packet does not execute.

< $***TMSCT***,23,3,StopAndClearBuffer(2),*56\r\n
// When receiving the command StopAndClearBuffer(2), if tag 1 does not finish

> $***TMSCT***,4,1,OK,*5C\r\n // Respond 1 OK
// It does not send out TMSTA tag number for finishing due to the clearing of the motion command and QueueTag().

> $***TMSCT***,4,3,OK,*5E\r\n // Respond 3 OK

It clears and exits the current Script 1 in execution, and clears all the Script programs in the Received Script buffer. Therefore, it clears Script 2 without the response to Script 2.

16. Modbus Functions

16.1 ModbusTCP Class

Use Modbus TCP class and declare variables to create a Modbus TCP device. The variable name will be the device name.

Construct 1

ModbusTCP *VariableName* = string, int, int
ModbusTCP *VariableName* = string, int
ModbusTCP *VariableName* = string

Parameters

string	remote host IP address	
int	remote host connection port	(502 by default)
int	read/write timeout in millisecond	0 .. 10000 (10000ms by default)

Note

```
ModbusTCP mtcp1 = "192.168.1.10"
  // construct a device, with IP 192.168.1.10
ModbusTCP mtcp2 = "192.168.1.10", 502
  // construct a device, with IP 192.168.1.10, Port 502
ModbusTCP mtcp3 = "192.168.1.10", 502, 8000
  // construct a device, with IP 192.168.1.10, Port 502, Timeout 8000ms
```

* After construction, either in flow projects or script projects, the device will not connect actively until proceeding to read or write.

Member Methods

Name	Description
Preset()	Configure the preset ModbusTCP parameters.
IODDPreset()	Read IODD file and configure the preset ModbusTCP parameters.

16.1.1 Preset()

Configure the preset ModbusTCP parameters.

Syntax 1

```
bool Preset(
    string,
    byte,
    string,
    int,
    string,
    int
)
```

Parameters

string	preset device name	
byte	Slave ID	
string	signal type	"DO", "DI", "RO", "RI"
int	starting address	

string type "bool", "byte", "int16", "int32", "float", "double", "string"
int suffix parameter, when type is
"int32" 0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
"float" 0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
"double" 0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
"string" address count (0 by default)
This is invalid for other types.

Return

bool preset successfully True, preset unsuccessfully False

Syntax 2

```
bool Preset(
    string,
    byte,
    string,
    int,
    string
)
```

Note

Same as syntax 1. Fill default to suffix parameter by default.

Note

```
ModbusTCP mbus1 = "127.0.0.1"
    // construct a device, with IP 127.0.0.1, Port 502, Timeout 8000ms

mbus1.Preset("light", 1, "DO", 7206, "bool")   // set preset device name to "light"
mbus1.Preset("9000", 1, "RO", 9000, "string")      // set preset device name to "9000"
    // Return error, naming must be in alphanumeric combination.

mbus1.Preset("preset_9000", 1, "RO", 9000, "int", 0)
    // set preset device name to "preset_9000" // Little Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "int", 1)
    // set preset device name to "preset_9000" // Big Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "int")
    // set preset device name to "preset_9000" // Big Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "string", 5)
    // set preset device name to "preset_9000" // string type
    // Once the name, preset_9000, exists, it overwrites the content to the configuration of the same
    name by the processing sequence.
bool flag = modbus_read("mbus1", "light")   // flag = false    // suppose camera light is off
modbus_write("mbus1", "light", true)        // write true      // camera light is on
flag = modbus_read("mbus1", "light")        // flag = true

modbus_write("mbus1 ", "preset_9000", Ctrl("\0\0\0\0\0\0\0\0\0\0"))
  // clears preset_9000 in string type and occupies five addresses (5 RO = 10 bytes)

modbus_write("mbus1", "preset_9000", 1234)   // write "1234"   // because preset_9000 is in
                                                string type
```

```
int var_i = modbus_read("mbus1", "preset_9000")      // var_i = 1234   // it tries to convert
                                                     "1234" to integer.
  // because preset_9000 is in string type and occupies five addresses, it then reads 10 bytes and converts
by strings. (ends when encountered 0x00.)

modbus_write("mbus1", "preset_9000", "HelloWorld")      // write "HelloWorld"
string var_s = modbus_read("mbus1", "preset_9000")      // var_s = "HelloWorld"
var_i = modbus_read("mbus1", "preset_9000")
// Return error, unable to convert HelloWorld to integer.

modbus_write("mbus1", "preset_9000", 1234)    // write "1234"
  // contiune the last piece of data and write "HelloWorld"    // therefore, the current data in the address
                                                               9000 is "1234oWorld"
var_i = modbus_read("mbus1", "preset_9000")
// Return error, unable to convert 1234oWorld to integer.
```

16.1.2 IODDPreset()

Read IODD file and configure the preset ModbusTCP parameters.

Syntax 1

```
bool IODDPreset(
    string,
    byte,
    int,
    int
)
```

Parameters

`string` IODD file name (read the IODD file stored in the directory .\XmlFiles\IODD at local host)

`byte` Slave ID

`int` starting address In

`int` starting address Out

Return

`bool` preset successfully True, preset unsuccessfully False

Note

```
ModbusTCP mbus1 = "192.168.1.10"
// construct a device, with IP 192.168.1.10, Port 502, Timeout 10000ms

mbus1.IODDPreset("OMRON-E2EQ-X3B4-IL2-20170301-IODD1.1.xml", 1, 100, 200)
  // load the file, .\XmlFiles\IODD\OMRON-E2EQ-X3B4-IL2-20170301-IODD1.1.xml, and add the preset
  configuration parameters.
  // define preset names in the same way as flow projects rules.
```

16.2 ModbusRTU Class

Use Modbus TCP class and declare variables to create a Modbus TCP device. The variable name will be the device name.

Construct

ModbusRTU *VariableName* = string, int, string, int, float, int, bool, bool, bool
ModbusRTU *VariableName* = string, int, string, int, float, int
ModbusRTU *VariableName* = string, int, string, int, float
ModbusRTU *VariableName* = string, int

Parameters

string	connection description		
int	bits per second, BaudRate		
string	parity check	"none", "odd", "even", "mark", "space"	("none" by default)
int	Data Bits	5, 6, 7, 8	(8 by default)
float	Stop Bits	1, 1.5, 2	(1 by default)
int	read/write timeout in millisecond	0 .. 10000	(10000 ms by default)
bool	DTR/DSR	true, false	(false by default)
bool	RTS/CTS	true, false	(false by default)
bool	XON/XOFF	true, false	(false by default)

Note

```
ModbusRTU mrtu1 = "COM2",115200
  // construct a device with Baudrate 115200
ModbusRTU mrtu2 = "COM2",115200,"none",8,1
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1
ModbusRTU mrtu3 = "COM2",115200,"none",8,1,10000
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1, Timeout 10000ms
```

* After construction, either in flow projects or script projects, the device will not connect actively until proceeding to read or write.

Member Methods

Name	Description
Preset()	Configure the preset ModbusTCP parameters.
IODDPreset()	Read IODD file and configure the preset ModbusTCP parameters.

16.2.1 Preset()

Configure the preset ModbusTCP parameters.

Syntax 1

```
bool Preset(
    string,
    byte,
    string,
    int,
    string,
    int
```

)

Parameters

string	preset device name	
byte	Slave ID	
string	signal type	"DO", "DI", "RO", "RI"
int	starting address	
string	type	"bool", "byte", "int16", "int32", "float", "double", "string"
int	suffix parameter, when type is	
	"int32"	0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
	"float"	0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
	"double"	0 Little Endian (CD AB) 1 Big Endian (AB CD) (default)
	"string"	address count (0 by default)
	This is invalid for other types.	

Return

bool preset successfully True，preset unsuccessfully False

Syntax 2

```
bool Preset(
    string,
    byte,
    string,
    int,
    string
)
```

Note

Same as syntax 1. Fill default to suffix parameter by default.

Note

```
ModbusRTU mbus1 = "COM2",115200
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1, Timeout 10000ms

mbus1.Preset("light", 1, "DO", 7206, "bool")        // set preset device name to "light"
mbus1.Preset("9000", 1, "RO", 9000, "string")       // set preset device name to "9000"
    // Return error, naming must be in alphanumeric combination.

mbus1.Preset("preset_9000", 1, "RO", 9000, "int", 0)
    // set preset device name to "preset_9000" // Little Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "int", 1)
    // set preset device name to "preset_9000" // Big Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "int")
    // set preset device name to "preset_9000" // Big Endian
mbus1.Preset("preset_9000", 1, "RO", 9000, "string", 5)
    // set preset device name to "preset_9000" // string type
    // Once the name, preset_9000, exists, it overwrites the content to the configuration of the same
    name by the processing sequence.

bool flag = modbus_read("mbus1", "light")   // flag = false    // suppose camera light is off
modbus_write("mbus1", "light", true)        // write true      // camera light is on
```

```
flag = modbus_read("mbus1", "light")          // flag = true

modbus_write("mbus1 ", "preset_9000", Ctrl("\0\0\0\0\0\0\0\0\0\0"))
  // clears preset_9000 in string type and occupies five addresses (5 RO = 10 bytes)

modbus_write("mbus1", "preset_9000", 1234)    // write "1234"    // because preset_9000 is in
                                              string type
int var_i = modbus_read("mbus1", "preset_9000")    // var_i = 1234    // it tries to convert
                                                   "1234" to integer.
  // because preset_9000 is in string type and occupies five addresses, it then reads 10 bytes and converts
by strings. (ends when encountered 0x00.)

modbus_write("mbus1", "preset_9000", "HelloWorld")      // write "HelloWorld"
string var_s = modbus_read("mbus1", "preset_9000")      // var_s = "HelloWorld"
var_i = modbus_read("mbus1", "preset_9000")
// Return error, unable to convert HelloWorld to integer.

modbus_write("mbus1", "preset_9000", 1234)    // write "1234"
  // contiune the last piece of data and write "HelloWorld"    // therefore, the current data in the address
                                                               9000 is "1234oWorld"
var_i = modbus_read("mbus1", "preset_9000")
// Return error, unable to convert 1234oWorld to integer.
```

16.2.2 IODDPreset()

Read IODD file and configure the preset ModbusTCP parameters.

Syntax 1

```
bool IODDPreset(
    string,
    byte,
    int,
    int
)
```

Parameters

string	IODD file name (read the IODD file stored in the directory .\XmlFiles\IODD at local host)
byte	Slave ID
int	starting address In
int	starting address Out

Return

bool preset successfully True, preset unsuccessfully False

Note

```
ModbusRTU mbus1 = "COM2",115200
  // construct a device with Baudrate 115200, Parity none, DataBits 8, StopBits 1, Timeout 10000ms

mbus1.IODDPreset("OMRON-E2EQ-X3B4-IL2-20170301-IODD1.1.xml", 1, 100, 200)
  // load the file, .\XmlFiles\IODD\OMRON-E2EQ-X3B4-IL2-20170301-IODD1.1.xml, and add the preset
  configuration parameters.
```

```
// define preset names in the same way as flow projects rules.
```

16.3 modbus_open()

Open the connection to the Modbus TCP/RTU device.

Syntax 1

bool **modbus_open**(
    string
)

Parameters

string	TCP/RTU device name	

Return

bool	True	Open successfully.
	False	Open unsuccessfully.

Note

```
ModbusTCP mbus1 = "127.0.0.1"   // construct a device, with IP 127.0.0.1, Port 502, Timeout 10000ms
modbus_open("mbus1")            // connect to the device with IP: 127.0.0.1 and port: 502.
```

16.4 modbus_close()

Close the connection from the Modbus TCP/RTU device.

Syntax 1

```
bool modbus_close(
    string
)
```

Parameters

string	TCP/RTU device name	

Return

bool	True	close successfully
	False	close unsuccessfully

Note

```
ModbusTCP mbus1 = "127.0.0.1"   // construct a device, with IP 127.0.0.1, Port 502, Timeout
                                   10000ms
modbus_open("mbus1")            // connect to the device with IP: 127.0.0.1 and port: 502.
modbus_close("mbus1")           // close the connection.
```

16.5 modbus_read()

Modbus TCP/RTU read function

Syntax 1 (TCP/RTU)

? **modbus_read**(
string,
string
)

Parameters

string TCP/RTU device name
string The predefined parameters belong to TCP/RTU device

Return

? The return data type is decided by the predefined parameters

Signal Type	Function Code	Type	Num Of Addr	Return data type
Digital Output	01	byte	1	byte (H: 1)(L: 0)
		bool	1	bool (H: true)(L: false)
Digital Input	02	byte	1	byte (H: 1)(L: 0)
		bool	1	bool (H: true)(L: false)
Register Output	03	byte	1	byte
		int16	1	int
		int32	2	int
		float	2	float
		double	4	double
		string	?	string
		bool	1	bool
Register Input	04	byte	1	byte
		int16	1	int
		int32	2	int
		float	2	float
		double	4	double
		string	?	string
		bool	1	bool

* According to the Little Endian (CD AB) or Big Endian (AB CD) setting, the int32, float, double data will transformed automatically.
* string will follows the UTF8 data format transformation (Stop at 0x00)

Note

Modbus Address data size
Digital 1 address = 1 bit size
Register 1 address = 2 bytes size

If the default values are applied in Preset Setting

preset_800	DO	800	byte	
preset_7202	DI	7202	bool	
preset_9000	RO	9000	string	4
preset_7001	RI	7001	float	Big-Endian (AB CD)

value = **modbus_read**("TCP_1", "preset_800") // value = 1 // DO 1 address = 1 bit

```
value = modbus_read("TCP_1", "preset_7202")  // value = true          // DI 1 address = 1 bit
value = modbus_read("TCP_1", "preset_9000")  // value = ab1234cd  // RO 4 address = 8 bytes size
value = modbus_read("TCP_1", "preset_7001")  // value = -314.1593  // RI 2 address = 4 bytes size (float)
```

Syntax 2 (TCP/RTU)

```
byte[] modbus_read(
    string,
    byte,
    string,
    int,
    int
)
```

Parameters

string	TCP/RTU Device Name	
byte	Slave ID	
string	Read type	
DO	Digital Output	(FC 01 Read Coil Status)
DI	Digital Input	(FC 02 Read Input Status)
RO	Register Output	(FC 03 Read Holding Registers)
RI	Register Input	(FC 04 Read Input Registers)
int	Starting address	
int	Data length	

Return

byte[] The returned byte array from Modbus server
*User defined modbus_read only follows Big-Endian (AB CD) format to read byte[]

Note

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4
TCP device	0	DI	7202	3
TCP device	0	RO	9000	6
TCP device	0	RI	7001	12
TCP device	0	RI	7301	6

```
value = modbus_read("TCP_1", 0, "DO", 800, 4)
    // value = {0,0,0,0}    // DO 4 address = 4 bit to byte array
value = modbus_read("TCP_1", 0, "DI", 7202, 3)
    // value = {1,0,0}          // DI 3 address = 3 bit to byte array
value = modbus_read("TCP_1", 0, "RO", 9000, 6)
    // value = {0x54,0x65,0x63,0x68,0x6D,0x61,0x6E,0xE9,0x81,0x94,0xE6,0x98}
```

```
    // RO 6 address = 12 bytes size
value = modbus_read("TCP_1", 0, "RI", 7001, 12)
    // value =
    {0x29,0x30,0x9F,0x4C,0xC3,0x7C,0x99,0x9A,0x44,0x5E,0xEC,0xCD,0x42,0xB4,0x00,0x00,
    0x80,0x00,0x00,0x00,0x00,0x00,0x00,0x00}       // RI 12 address = 24 bytes size
value = modbus_read("TCP_1", 0, "RI", 7301, 6)
    // value = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x0A,0x00,0x39}
    // RI 6 address = 12 bytes size
```

16.6 modbus_read_int16()

Modbus TCP/RTU read function, and transform Modbus address data array to int16 array

Syntax 1 (TCP/RTU)

int[] **modbus_read_int16**(
string,
byte,
string,
int,
int,
int
)

Parameters

string	TCP/RTU Device Name		
byte	Slave ID		
string	Read type		
	DO	Digital Output	(FC 01 Read Coil Status)
	DI	Digital Input	(FC 02 Read Input Status)
	RO	Register Output	(FC 03 Read Holding Registers)
	RI	Register Input	(FC 04 Read Input Registers)
int	Starting address		
int	Data length		
int	Follows Little Endian (CD AB) or Big Endian (AB CD) to transform the address data to int16 array. *Invalid Parameter. Only support int32, float, double		
	0	Little Endian	
	1	Big Endian (Default)	

Return

int[]	The returned int array from Modbus server

Syntax 2 (TCP/RTU)

int[] **modbus_read_int16**(
string,
byte,
string,
int,
int
)

Note

Similar to Syntax1 with Big Endian (AB CD) setting
modbus_read_int16("TCP_1", 0, "DI", 7200, 2) => **modbus_read_int16**("TCP_1", 0, "DI", 7200, 2, 1)
Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4
TCP device	0	DI	7202	3
TCP device	0	RO	9000	6
TCP device	0	RI	7001	12
TCP device	0	RI	7301	6

```
value = modbus_read_int16("TCP_1", 0, "DO", 800, 4)
    // byte[] = {0,0,0,0}    to int16[]   value = {0,0}     // byte[0][1] , byte[2][3]
value = modbus_read_int16("TCP_1", 0, "DI", 7202, 3)
    // byte[] = {1,0,0}              to int16[]   value = {256,0}
    // byte[0][1] , byte[2][3] // Fill up to [3] automatically
value = modbus_read_int16("TCP_1", 0, "RO", 9000, 6)
    // byte[] = {0x54,0x65,0x63,0x68,0x6D,0x61,0x6E,0xE9,0x81,0x94,0xE6,0x98}
    // to int16[] value = {21605,25448,28001,28393,-32364,-6504}
value = modbus_read_int16("TCP_1", 0, "RI", 7001, 12)
    // byte[] =
{0x29,0x30,0x9F,0x4C,0xC3,0x7C,0x99,0x9A,0x44,0x5E,0xEC,0xCD,0x42,0xB4,0x00,0x00,
                0x80,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // to int16[] value = {10544,-24756,-15492,-26214,17502,-4915,17076,0,-32768,0,0,0}
value = modbus_read_int16("TCP_1", 0, "RI", 7301, 6)
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x31,0x00,0x23}
    // to int16[] value = {2018,5,18,15,49,35}
value = modbus_read_int16("TCP_1", 0, "RI", 7301, 6, 0)
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x31,0x00,0x23}
    // to int16[] value = {2018,5,18,15,49,35}
```

16.7 modbus_read_int32()

Modbus TCP/RTU read function, and transform Modbus address data array to int32 array

Syntax 1 (TCP/RTU)

int[] **modbus_read_int32**(
string,
byte,
string,
int,
int,
int
)

Parameters

string	TCP/RTU DEVICE NAME		
byte	Slave ID		
string	Read type		
	DO	Digital Output	(FC 01 Read Coil Status)
	DI	Digital Input	(FC 02 Read Input Status)
	RO	Register Output	(FC 03 Read Holding Registers)
	RI	Register Input	(FC 04 Read Input Registers)
int	Starting address		
int	Data length		
int	Follows Little Endian (CD AB) or Big Endian (AB CD) to transform the address data to int32 array.		
	0	Little Endian	
	1	Big Endian (Default)	

Return

int[]	The returned int array from Modbus server

Syntax 2 (TCP/RTU)

int[] **modbus_read_int32**(
string,
byte,
string,
int,
int
)

Note

Similar to Syntax1 with Big Endian (AB CD) setting.
modbus_read_int32("TCP_1", 0, "DI", 7200, 2) => **modbus_read_int32**("TCP_1", 0, "DI", 7200, 2, 1)
Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4

TCP device	0	DI	7202	3
TCP device	0	RO	9000	6
TCP device	0	RI	7001	12
TCP device	0	RI	7301	6

```
value = modbus_read_int32("TCP_1", 0, "DO", 800, 4)
    // byte[] = {0,0,0,0}     to int32[]   value = {0}// byte[0][1][2][3]
value = modbus_read_int32("TCP_1", 0, "DI", 7202, 3)
    // byte[] = {1,0,0}       to int32[]   value = {16777216}
    // byte[0][1][2][3] // Fill up to [3] automatically.
value = modbus_read_int32("TCP_1", 0, "RO", 9000, 6)
    // byte[] = {0x54,0x65,0x63,0x68,0x6D,0x61,0x6E,0xE9,0x81,0x94,0xE6,0x98}
    // to int32[] value = {1415930728,1835101929,-2120948072}
value = modbus_read_int32("TCP_1", 0, "RI", 7001, 12)
    // byte[] =
    {0x29,0x30,0x9F,0x4C,0xC3,0x7C,0x99,0x9A,0x44,0x5E,0xEC,0xCD,0x42,0xB4,0x00,0x00,
            0x80,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // to int32[] value = {691052364,-1015244390,1147071693,1119092736,-2147483648,0}
value = modbus_read_int32("TCP_1", 0, "RI", 7301, 6)
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x31,0x00,0x23}
    // to int32[] value = {132251653,1179663,3211299}
value = modbus_read_int32("TCP_1", 0, "RI", 7301, 6, 0)// byte[2][3][0][1]
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x31,0x00,0x23}
    // to int32[] value ={0x000507E2,0x000F0012,0x00230031} = {329698,983058,2293809}
```

16.8 modbus_read_float()

Modbus TCP/RTU read function, and transform Modbus address data array to float array

Syntax 1 (TCP/RTU)

float[] **modbus_read_float**(
string,
byte,
string,
int,
int,
int
)

Parameters

string	TCP/RTU DEVICE NAME		
byte	Slave ID		
string	Read type		
	DO	Digital Output	(FC 01 Read Coil Status)
	DI	Digital Input	(FC 02 Read Input Status)
	RO	Register Output	(FC 03 Read Holding Registers)
	RI	Register Input	(FC 04 Read Input Registers)
int	Starting address		
int	Data length		
int	Follows Little Endian (CD AB) or Big Endian (AB CD) to transform the address data to float array.		
	0	Little Endian	
	1	Big Endian (Default)	

Return

float[]	The returned float array from Modbus server

Syntax 2 (TCP/RTU)

float[] **modbus_read_float**(
string,
byte,
string,
int,
int
)

Note

Similar to Syntax1 with Big Endian (AB CD) setting.
modbus_read_float("TCP_1", 0, "DI", 7200, 2) => **modbus_read_float**("TCP_1", 0, "DI", 7200, 2, 1)

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4
TCP device	0	DI	7202	3
TCP device	0	RO	9000	6
TCP device	0	RI	7001	12
TCP device	0	RI	7301	6

```
value = modbus_read_float("TCP_1", 0, "DO", 800, 4)
    // byte[] = {0,0,0,0}    to float[]    value = {0}// byte[0][1][2][3]
value = modbus_read_float("TCP_1", 0, "DI", 7202, 3)
    // byte[] = {1,0,0}      to float[]    value = {2.350989E-38}    // byte[0][1][2][3]
    // Fill up to [3] automatically.
value = modbus_read_float("TCP_1", 0, "RO", 9000, 6)
    // byte[] = {0x54,0x65,0x63,0x68,0x6D,0x61,0x6E,0xE9,0x81,0x94,0xE6,0x98}
    // to float[]        value = {3.940861E+12,4.360513E+27,-5.46975E-38}
value = modbus_read_float("TCP_1", 0, "RI", 7001, 12)
    // byte[] =
    {0x29,0x30,0x9F,0x4C,0xC3,0x7C,0x99,0x9A,0x44,0x5E,0xEC,0xCD,0x42,0xB4,0x00,0x00,
            0x80,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // to float[]        value = {3.921802E-14,-252.6,891.7,90,0,0}
value = modbus_read_float("TCP_1", 0, "RI", 7001, 12, 0)      // byte[2][3][0][1]
    // to float[]        value =
    {0x9F4C2930,0x999AC37C,0xECCD445E,0x000042B4,0x00008000,0x00000000}
                      = {-4.323275E-20,-1.600218E-23,-1.985221E+27,2.392857E-41,4.591775E-
                      41,0}
value = modbus_read_float("TCP_1", 0, "RI", 7301, 6)
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x0F,0x00,0x3A,0x00,0x26}
    // to float[]        value = {3.400471E-34,1.65306E-39,5.326512E-39}
```

16.9 modbus_read_double()

Modbus TCP/RTU read function, and transform Modbus address data array to double array.

Syntax 1 (TCP/RTU)

double[] **modbus_read_double**(
    string,
    byte,
    string,
    int,
    int,
    int
)

Parameters

string	TCP/RTU DEVICE NAME		
byte	Slave ID		
string	Read type		
	DO	Digital Output	(FC 01 Read Coil Status)
	DI	Digital Input	(FC 02 Read Input Status)
	RO	Register Output	(FC 03 Read Holding Registers)
	RI	Register Input	(FC 04 Read Input Registers)
int	Starting address		
int	Data length		
int	Follows Little Endian (CD AB) or Big Endian (AB CD) to transform the address data to double array.		
	0	Little Endian	
	1	Big Endian (Default)	

Return

double[] The returned double array from Modbus server

Syntax 2 (TCP/RTU)

double[] **modbus_read_double**(
    string,
    byte,
    string,
    int,
    int
)

Note

Similar to Syntax1 with Big Endian (AB CD) setting.
modbus_read_double("TCP_1", 0, "DI", 7200, 2) => **modbus_read_double**("TCP_1", 0, "DI", 7200, 2, 1)

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4
TCP device	0	DI	7202	3
TCP device	0	RO	9000	6
TCP device	0	RI	7001	12
TCP device	0	RI	7301	6

```
value = modbus_read_double("TCP_1", 0, "DO", 800, 4)
    // byte[] = {0,0,0,0}    to double[]      value = {0}// byte[0][1][2][3][4][5][6][7]
value = modbus_read_double("TCP_1", 0, "DI", 7202, 3)
    // byte[] = {1,0,0}      to double[]      value = {7.2911220195564E-304}
    // byte[0][1][2][3][4][5][6][7]
value = modbus_read_double("TCP_1", 0, "RO", 9000, 6)
    // byte[] = {0x54,0x65,0x63,0x68,0x6D,0x61,0x6E,0xE9,0x81,0x94,0xE6,0x98}
    // to double[]    value = {3.65481260356117E+98,-4.87647898854073E-301}
value = modbus_read_double("TCP_1", 0, "RI", 7001, 12)
    // byte[] =
    {0x29,0x30,0x9F,0x4C,0xC3,0x7C,0x99,0x9A,0x44,0x5E,0xEC,0xCD,0x42,0xB4,0x00,0x00,
            0x80,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // to double[]    value = {2.76472410615396E-110,2.2818627604613E+21,0}
value = modbus_read_double("TCP_1", 0, "RI", 7001, 12, 0)  // byte[6][7][4][5][2][3][0][1]
    // to double[]    value = {0x999AC37C9F4C2930,0x000042B4ECCD445E,0x0000000000008000}
                      = {-2.4604103205376E-185,3.62371629877526E-310,1.6189543082926E-319}
value = modbus_read_double("TCP_1", 0, "RI", 7301, 6)
    // byte[] = {0x07,0xE2,0x00,0x05,0x00,0x12,0x00,0x10,0x00,0x0B,0x00,0x29}
    // to double[]    value = {1.06475148078395E-270,1.52982527955113E-308}
```

16.10 modbus_read_string()

Modbus TCP/RTU read function, and convert Modbus address data array to string text in UTF8

Syntax 1 (TCP/RTU)

```
string modbus_read_string(
    string,
    byte,
    string,
    int,
    int,
    int
)
```

Parameters

string	TCP/RTU DEVICE NAME		
byte	Slave ID		
string	Read type		
	DO	Digital Output	(FC 01 Read Coil Status)
	DI	Digital Input	(FC 02 Read Input Status)
	RO	Register Output	(FC 03 Read Holding Registers)
	RI	Register Input	(FC 04 Read Input Registers)
int	Starting address		
int	Data length		
int	Follows Little Endian (CD AB) or Big Endian (AB CD) to transform the address data to string. *Invalid Parameter. Only support int32, float, double. String follows UTF8 and is sequentially transferred according to address.		
	0	Little Endian	
	1	Big Endian (Default)	

Return

string	The returned UTF8 string from Modbus server (Stop at 0x00)

Syntax 2 (TCP/RTU)

```
string modbus_read_string(
    string,
    byte,
    string,
    int,
    int
)
```

Note

Similar to Syntax1 with Big Endian (AB CD) setting.

modbus_read_string("TCP_1", 0, "RO", 9000, 2) => **modbus_read_string**("TCP_1", 0, "RO", 9000, 2, 1)

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	RO	9000	12

```
modbus_write("TCP_1", 0, "RO", 9000) = "1234 達明机器手臂"
        // Undefined numbers of addresses to write, the default value 0 denotes to write the complete
        data length of 22 bytes.
        // Write byte[] = {0x31,0x32,0x33,0x34,0xE9,0x81,0x94,0xE6,0x98,0x8E,
                           0xE6,0x9C,0xBA,0xE5,0x99,0xA8,0xE6,0x89,0x8B,0xE8,0x87,0x82}
value = modbus_read_string("TCP_1", 0, "RO", 9000, 3)
        // byte[] = {0x31,0x32,0x33,0x34,0xE9,0x81}      // RO 3 address = 6 bytes size
        // to string = 1234
value = modbus_read_string("TCP_1", 0, "RO", 9000, 6)
        // byte[] = {0x31,0x32,0x33,0x34,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0x9C}
        // to string = 1234 達明
value = modbus_read_string("TCP_1", 0, "RO", 9000, 12)
        // byte[] = {0x31,0x32,0x33,0x34,0xE9,0x81,0x94,0xE6,0x98,0x8E,
                     0xE6,0x9C,0xBA,0xE5,0x99,0xA8,0xE6,0x89,0x8B,0xE8,0x87,0x82, 0x41,0x42}
        // to string = 1234 達明机器手臂 AB    // UTF8 format conversion
        // The ending, 0x00, will not be included when writing data. When reading 12 addresses, it will
        read beyond the range.
modbus_write("TCP_1", 0, "RO", 9000) = "1234"+Ctrl("\0")
        // Write byte[] = {0x31,0x32,0x33,0x34,0x00}      // Needs to write 3 Register address
value = modbus_read_string("TCP_1", 0, "RO", 9000, 5)
        // byte[] = {0x31,0x32,0x33,0x34,0x00,0x00, 0x94,0xE6,0x98,0x8E}     // The last 4 values are
        the original data at those addresses
        // to string = 1234      // UTF8 format conversion stops at 0x00
```

16.11 modbus_write()

Modbus TCP/RTU write function

Syntax 1 (TCP/RTU)

bool **modbus_write**(
    string,
    string,
    ?,
    int
)

Parameters

string TCP/RTU Device Name

string TCP/RTU The predefined parameters belong to TCP/RTU device

? The input data. The predefined parameters will be applied according to the table below.

Signal Type	Function Code	Type	Input type	Input value
Digital Output	05	byte	byte	(H: 1)(L: 0)
		bool	bool	(H: true)(L: false)
Register Output	06	byte	byte	
		bool	bool	
		int16	int	
Register Output	16	int32	int	
		float	float	
		double	double	
		string	string	

* int32, float, double will be transferred with Little Endian (CD AB) or Big Endian (AB CD) according to user's setting.

* string will be transferred with UTF8 format

* Writing array value is not supported with predefined parameters. To write with the array value, user defined method should be applied (Syntax 3/4)

int The maximum number of addresses to be write, only effective to string type data

> 0 Valid address length. Write with defined address length

<= 0 Invalid address length. Write all the data

When this parameter is skipped (As shown in Syntax2), the predefined address length will be applied.

Return

bool True Write success

False Write failed 1. If the input data ? is empty string or array

2. If an error occurred in Modbus communication

Syntax 2 (TCP/RTU)

bool **modbus_write**(
    string,
    string,
    ?,

)

Note

Similar to Syntax1 with predefined address length to write. If the predefined address length <= 0, it will write all the data.

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

preset_800	DO	800	bool
preset_9000	RO	9000	string 4

```
modbus_write("TCP_1", "preset_800", 1)          // write 1 (true)
modbus_write("TCP_1", "preset_800", 0)          // write 0 (false)
bool flag = true
modbus_write("TCP_1", "preset_800", flag)       // write 1 (true)
modbus_write("TCP_1", "preset_800", false)      // write 0 (false)

string ss = "ABCDEFGHIJKLMNOPQRST"    // With no number of address, the predefined
                                       address length, 4, is applied. That is 4 RO = 8 bytes size
                                       can be written.
modbus_write("TCP_1", "preset_9000", ss) // write ABCDEFGH   // The exceeding part will be
                                       skipped
                                       // With no number of address, the predefined address
                                       length, 4, is applied. That is 4 RO = 8 bytes size can be
                                       written.
modbus_write("TCP_1", "preset_9000", "1234567")  // write 1234567\0     // Use 0x00 to fill up
                                                    4 address
                                                    // With address length = 0, write all the data.
                                                    "09AB123" needs 4 addresses.
modbus_write("TCP_1", "preset_9000", "09AB123", 0)    // write 09AB123\0     // Use 0x00 to
                                                    fill up 4 address
                                                    // With address length = 5, write data in 5
                                                    addresses. That is 5 RO = 10 bytes size can
                                                    be wrote.
modbus_write("TCP_1", "preset_9000", "09AB1234", 5)  // write 09AB1234      // The input
                                                    data needs only 4 addresses.
```

Syntax 3 (TCP/RTU)

```
bool modbus_write(
    string,
    byte,
    string,
    int,
    ?,
    int
)
```

Parameters

string TCP/RTU DEVICE NAME

byte Slave ID

string Write type

DO	Digital Output	(FC 05/15 Write Single/Multiple Coil(s))
RO	Register Output	(FC 06/16 Write Single/Multiple Register(s))

int Starting address

? Input data

Signal Type	Function Code	Input ? type	Input value
Digital Output	05	byte	(H: 1)(L: 0)
		bool	(H: true)(L: false)
Digital Output	15	byte[]	(H: 1)(L: 0)
		bool[]	(H: true)(L: false)
Register Output	06	byte	
		bool	
Register Output	16	int	
		float	
		double	
		string	
		byte[]	
		int[]	
		float[]	
		double[]	
		string[]	
		bool[]	

*User defined modbus_write will follows Big-Endian (AB CD) format to write

* Here int means int32. For int16 type data, GetBytes() needs to be applied first to change int16 to byte[]

int The maximum number of addresses to be write, only effective to string type data

> 0	Valid address length. Write with defined address length
<= 0	Invalid address length. Write all the data

Return

bool

True	Write success	
False	Write failed	1. If the input data ? is empty string or array 2. If an error occurred in Modbus communication

Syntax 4 (TCP/RTU)

```
bool modbus_write(
    string,
    byte,
    string,
    int,
    ?
)
```

Note

Similar to Syntax3 with address length <= 0, it will write all the data.

modbus_write("TCP_1", 0, "RO", 9000, bb) => **modbus_write**("TCP_1", 0, "RO", 9000, bb, 0)

Modbus Address data size

Digital	1 address = 1 bit size
Register	1 address = 2 bytes size

If the user defined values are applied to User Setting as

TCP device	0	DO	800	4
TCP device	0	RO	9000	12

```
byte[] bb = {10, 20, 30}
modbus_write("TCP_1", 0, "DO", 800,    bb)       // write 1,1,1
                                                  // Zero value, write 0. Non-zero value, write 1.
modbus_write("TCP_1", 0, "DO", 800, bb, 2)       // write 1,1
                                                  // Address number = 2, only write 2 addresses.
modbus_write("TCP_1", 0, "DO", 800, true)        // write 1
int i = 10000
modbus_write("TCP_1", 0, "RO", 9000, i)          // write 0x00,0x00,0x27,0x10
                                                  // with int32 BigEndian (AB CD) default
bb = GetBytes(i, 0, 1)                            // bb = {0x10,0x27}
                                                  // transfer to int16 LittleEndian (CD AB)
modbus_write("TCP_1", 0, "RO", 9000, bb)         // write 0x10,0x27
string[] n = {"ABC", "12", "34"}
modbus_write("TCP_1", 0, "RO", 9000, n, 2)       // write ABC1
                                                  // Only 2 addresses available, the exceeding values
                                                  cannot be applied.
modbus_write("TCP_1", 0, "RO", 9000, n, 5)       // write ABC12340
                                                  // The data needs 4 addresses (0xAB 0xC1 0x23 -
                                                  0x40)
```

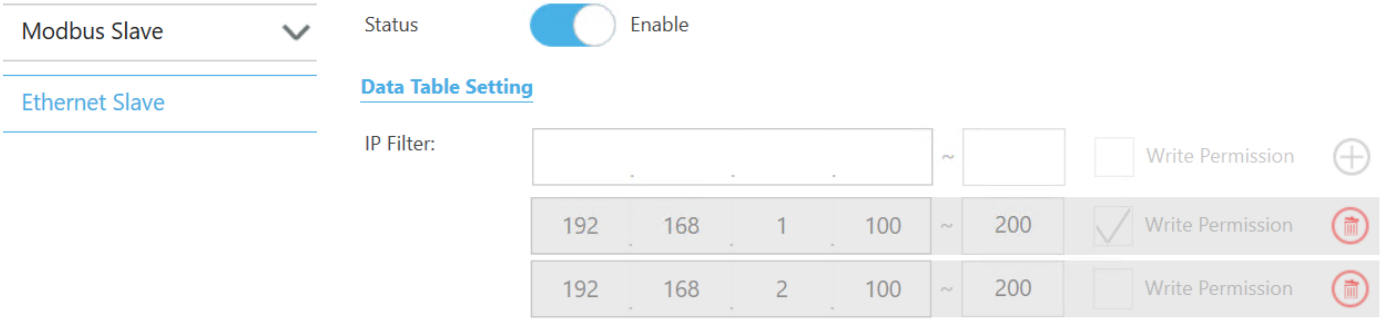
17. TM Ethernet Slave

Ethernet Slave comes with functions established with Socket TCP based on the framework of client/server connections. Once enabled, the robot establishes a Socket TCP Listener Serve to send the robot status and data to all of the connected clients or receive the contents from the clients to execute the respective instructions and update the respective information periodically and promptly without the real-time guarantee.

Like the Modbus Slave, the Ethernet Slave will automatically start on its own after power cycling if it was previously set to **Enable**. The established IP and Port will be shown in the notice window.

IP TMflow → System → Network → IP Address
Port 5891

17.1 GUI Setting



Enable/Disable Enable or disable Ethernet Slave

IP Filter IP whitelist
Sets ranges for eligible IP addresses that are allowed to connect to the Ethernet Slave. If no filters are set, all devices on the network can connect to the Ethernet Slave.

Write Permission If checked, allows devices within the corresponding IP range to write to the Ethernet Server with TMSVR commands.

For example, setting IP Filter.

Group 1 192.168.1.100 ~ 200 denotes IP 192.168.1.100, 192.168.1.101, … , and 192.168.1.200 are available for connections.
Group 2 192.168.2.100 ~ 200 denotes IP 192.168.2.100, 192.168.2.101, … , and 192.168.2.200 are available for connections.
If the IP address of the client is not in the range of the IPs listed above, it rejects the client to connect.

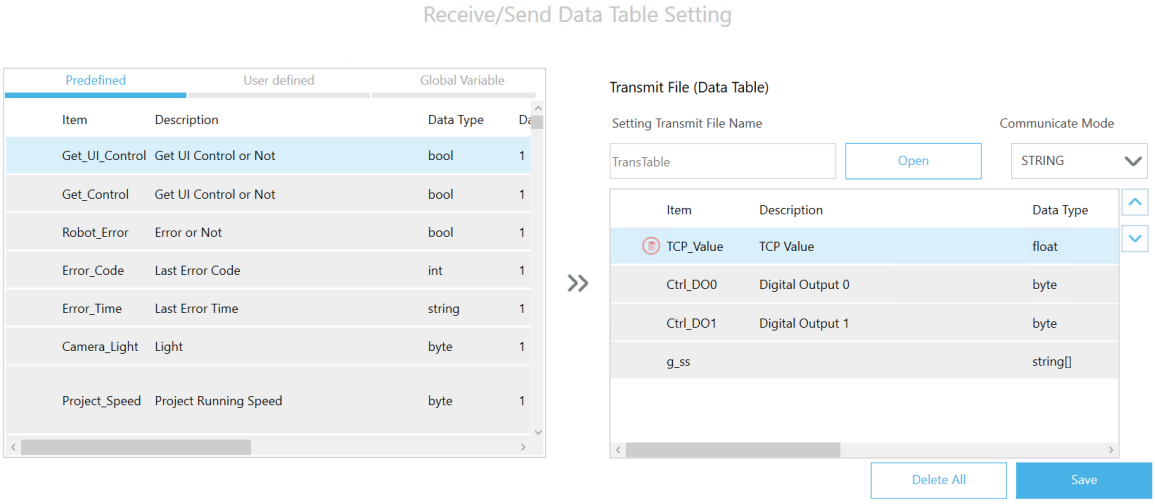
Group 1, 192.168.1.100 ~ 200, has permission to write, so clients connecting within this group range sending data to Ethernet Slave makes Ethernet Slave write data. Group 2, 192.168.2.100 ~ 200, does not have permission to write. When sending data to Ethernet Slave, it does not write data and will respond with the error code of write permission.

17.2 Data Table

Users can use the items listed the Data Table to customize the required data content as well as configure the communication protocol to transmit between the Ethernet Slave and clients, and save the settings as a communication file. When the Ethernet Slave is enabled, the data items in the communication file will be established with the relevant data content to the item to send to the connected clients periodically (no real-time guarantee). The types of the data format is defined by the settings in the communication file. The client can send data to the server with any type of the supported data formats.

In the protocol, the types of the supported data format are:

BINARY Binary format, converse in Byte array (Little Endian / UTF8)
STRING String format, similar to the external command format
JSON JSON string format



The configuration interface is a left-to-right mechanism. Users can add items at the left to the communication data table at the right and adjust the arrangement order of each item in the communication data table at the right. In the content to send, there will always be an item, ***Robot_Link***, predefined in Ethernet Slave as a type of byte with the attribute of read-only to denote whether to connect to the robot.

1. *Predefined*

Items and settings in this section are defined by TMflow, and the data content of the items is updated by TMflow. The defined items are the general statuses of the robot, such as the coordinates of the robot, the state of the project, the state of the electrical control box, or the IO related statuses, such as digital input / digital output, analog input / analog output.

2. *User defined*

Items and settings in this section are defined by TMflow users for project programs to read / write item data through the Expression Editor or for external users to read / write item data through the TMSVR commands over a TCP/IP connection. With the user defined tab, the project programs can work with external communication devices as a data exchange protocol. The item list in the user-defined tab can be saved as a custom-defined fil to be edited or exchanged data in the future.

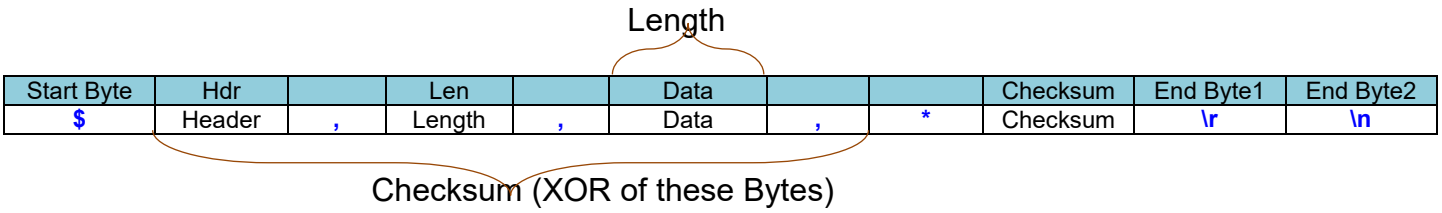
3. *Global Variable*

In the global variable tab, the variable list created by the TMflow users provides a way to directly use the variable name for read / write operations in the project programming, and the external communication devices can read / write global variables with the communication protocol.

4. *TransmitFile*

When the Ethernet Slave starts up, it will create the data content of the associated item by the list of items in the selected communication file and send the content to the connected client according to a fixed cycle. The Data section format will follow the specifications defined in the communication file. The Ext?_DO_Mask and Ext?_AO_Mask in the Predefined System Definition Area are primarily used by the client to transmit data to the server along with their associated Ext?_DO and Ext?_AO. Since they are intended solely for client-to-server communication, Ext?_DO_Mask and Ext?_AO_Mask are not in the periodic communication data table.

17.3 Communication Protocol



Name	Size	ASCII	HEX	Description
Start Byte	1	$	0x24	Start Byte for Communication
Header	*X*			Header for Communication
Separator	1	,	0x2C	Separator between Header and Length
Length	*Y*			Length of Data
Separator	1	,	0x2C	Separator between Length and Data
Data	*Z*			Communication Data
Separator	1	,	0x2C	Separator between Data and Checksum
Sign	1	*	0x2A	Begin Sign of Checksum
Checksum	*2*			Checksum of Communication
End Byte 1	1	\r	0x0D	
End Byte 2	1	\n	0x0A	End Byte of Communication

*Using the same communication protocol with external commands.

1. *Header*

Defines the purpose of communication packets. Different headers come with different definitions of communication packets and data.

- *TMSVR* Defines the function of TM Ethernet Slave
- *CPERR* Defines the errors of the communication packets such as packer errors, checksum errors, header errors, and so on.
  *Using the same content definitions with CPERR in external commands.

2. *Length*

The length indicates the length in the UTF8 bytes occupied by Data. Users can use decimal, hexadecimal, or binary format. The maximum length is 32 bits.
For example,

```
$TMSVR,100,Data,*CS\r\n      // 100 in decimal indicates the data length is 100 bytes
$TMSVR,0x100,Data,*CS\r\n    // 0x100 in hexadecimal indicates the data length is 256 bytes
$TMSVR,0b100,Data,*CS\r\n    // 0b100 in binary indicates the data length is 4 bytes
$TMSVR,8,1,達明,*CS\r\n      // indicates the length of Data,  1,達明, is 8 bytes (UTF8)
```

3. *Data*

The communication packet can contain any characters (0x00–0xFF, using UTF-8 encoding), with the data length determined by the Length field. The purpose and description of the Data must follow the Header definition.

4. Checksum

The checksum of the communication packet. The calculation method is XOR (exclusive OR). The calculation range is all Bytes between $ and * (excluding $ and *) as shown below.

$TMSVR,100,Data,*CS\r\n

Checksum = Byte[1] ^ Byte[2] … ^ Byte[N-6]

The checksum format is set to 2 bytes in hexadecimal (but not 0x), such as

$TMSVR,5,10,OK,*7E

CS = 0x54 ^ 0x4D ^ 0x53 ^ 0x56 ^ 0x52 ^ 0x2C ^ 0x35 ^ 0x2C ^ 0x31 ^ 0x30 ^ 0x2C ^ 0x4F ^ 0x4B ^ 0x2C = 0x7E

CS = 7E (0x37 0x45)

17.4 TMSVR

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*TMSVR*	,	Length	,	Data	,	*	Checksum	\r	\n

ID		Mode		Content
Transaction ID	,	0/1/2/3/ 11/12/13	,	Item and Value

TMSVR is defined as the TM Ethernet Slave protocol. The Data section of the packet is further divided into three segments, ID (Transaction ID), Mode (Content Mode), and Content (Item and Value), separated with commas and described below.

ID The transaction number expressed in any alphanumeric characters. (Reports the CPERR 04 error if a non-alphanumeric byte is encountered.) When used as a communication packet response, it is a transaction number that identifies which group of commands to respond.

, the symbol to separate

Mode The mode as the format of the data content

- 0 Indicates the server responds to the client command in string format.
- 1 Indicates the content data type in binary format
- 2 Indicates the content data type in string format
- 3 Indicates the content data type in JSON format
- 11 Indicates the content data type in binary format (Request read)
- 12 Indicates the content data type in string format (Request read)
- 13 Indicates the content data type in JSON format (Request read)
- 1/2/3 are for client write to server and client read from server. The client read from server is that the server sends contents to the connected client periodically.
- 11/12/13 are for client read from server with request read, which is the client sends read request for the item and the server responds with the item value to the client.

, the symbol to separate

Content The data content. Formatted by the mode definition.

Note

TMSVR command is for the client and the server to communicate in both directions. Under normal circumstances, the server will broadcast the data items from the Transmit and User Defined communication files to the connected clients periodically. When the server sends to the client, the data is sent to the client to read from the server with no response to the server required. When the client sends to the server, the data is received by the server from the client to write with response to the client required.

- ID Transaction Number

When the server sends data, cycles from 0 to 9 with each iteration. When the client sends data to the server, the transaction number can be in any alphanumeric characters customized at the client side. If the communication packet format is checked and correct , the server will reply the client with the command processing status by the transaction number in the packet.

- Mode Format and Mode for the Data Content

When the Mode is 1/2/3, it can be the function of client write to server or client read from server, in which client read from server means the server sends content to the connected client periodically. If client write to server, it means the clients sends data writing to the server. When the client sends an item to write, not only can one item be written, but multiple items at a time, and the server will send the command processing status according to the format of Mode 0.

When the Mode is 11/12/13, the request read method is used. The client sends an item request and the server responds to the item value. The purpose is to get the other item data not in the communication data table sent periodically. When the client sends a request to read, not only can one item be retrieved, but multiple items at a time. When the request succeeds, the server will send the item value to the client associated to the format of Mode 11/12/13. However, if the request fails, for example, the item name does not exist, the server will send the command processing status according to the format of Mode 0.

Whether data to write or request to read, the items can be all in the Predefined area but not limited to saving in the data table. However, in the Userdefined area and the GlobalVariable area, for the sake of custom definitions, it still need to be saved in the data table to proceed with writing or reading.

- Writing or Reading Confirmation

When the client sends data writing or reading requests to the server, no matter what format the data table used to proceed sending periodically, the servers supports to the data format of Mode 1/2/3/11/12/13 concurrently and checks whether all the criteria are correct before performing the request. If there is any error with the write command, no request will be performed. The criteria to write for inspection are:

1. The validity of the mode as the format of the data content
2. The connected client's write permissions based on the IP Filter.
3. The data content matches to the mode.
4. The item to write or read exists.
5. The attribute of the item to write is not read only.
6. The robot is in the appropriate mode (M/A).
7. The written data matches the data type of each item.

17.4.1 Mode = 0 (the status the server responds to the client command processing)

After the server receives and processes a write command from a client, it will respond with another TMSVR command with Mode 0. The details for Mode 0 are as follows.

Data

ID		Mode		Error Code		Error Description
Transaction ID	,	***0***	,	00 .. 07	,	

Transaction ID Defined while the client sends the command for the server to reply with.
Mode 0 for the server to respond to the client
Error Code Error code definitions. Fixed as 2 bytes and in hexadecimal (but not 0x)

00 Correct writing. No error.
01 The communication format or mode is not supported. (Ex. Mode = 99)
02 The connected client is not permitted to write. (IP filer without write permission)
03 The communication format and the data content format are mismatched.
(Ex. Mode = 3, but the data content is not in JSON format)
04 Item to write or read does not exist.
05 Unable to write to read-only items.
06 Incorrect M/A mode while writing.
07 Values to write mismatches with the configured type or the size.

Error Description Error description, following the error code.
00 OK
01 NotSupport
02 WritePermission
03 InvalidData
04 NotExist;XXX // ;XXX denotes which data item
05 ReadOnly;XXX
06 ModeError;XXX
07 ValueError;XXX

< $***TMSVR***,15,S0,*2*,Ctrl_DO0=1,*76\r\n // transaction ID S0, string format, set Ctrl_DO0=1
> $***TMSVR***,10,S0,*0*,00,OK,*18\r\n
// server responds transaction ID S0, mode 0, error code 00, correct writing

< $***TMSVR***,16,S1,*99*,Ctrl_DO0=1,*46\r\n // transaction ID S1, mode 99
> $***TMSVR***,18,S1,*0*,01,NotSupport,*0E\r\n
// server responds transaction ID S1, mode 0, error code 01, mode not support

< $***TMSVR***,15,S2,*2*,Ctrl_DO0=1,*74\r\n // transaction ID S2, string format, set Ctrl_DO0=1
> $***TMSVR***,23,S2,*0*,02,WritePermission,*6A\r\n
// server responds transaction ID S2, mode 0, error code 02, the connected client is not granted with write permission.

< $***TMSVR***,15,S3,*3*,Ctrl_DO0=1,*74\r\n // transaction ID S3, JSON format, set Ctrl_DO0=1
> $***TMSVR***,19,S3,*0*,03,InvalidData,*74\r\n
// server responds transaction ID S3, mode 0, error code 03, JSON format, data format (JSON) mismatched with the content data format (STRING)

< $***TMSVR***,16,S4,*2*,Ctrl_DO32=1,*40\r\n // transaction ID S4, string format, set Ctrl_DO32=1
> $***TMSVR***,26,S4,*0*,04,NotExist;Ctrl_DO32,*58\r\n
// server responds transaction ID S4, mode 0, error ode 04, item Ctrl_DO32 does not exist.

< $***TMSVR***,17,S5,*2*,Robot_Link=1,*07\r\n
// transaction ID S5, string format, set Robot_Link=1
> $***TMSVR***,27,S5,*0*,05,ReadOnly;Robot_Link,*1E\r\n
// server responds transaction ID S5, mode 0, error code 05, the item Robot_Link is read only.

Supposed the user defined Item: adata, Type: int, Size: 4, and Write: Auto.

< $***TMSVR***,20,S6,*2*,adata={1,2,3,4},*55\r\n
// transaction ID S6, string format, set adata={1,2,3,4}

> $***TMSVR***,23,S6,*0*,06,ModeError;adata,*2D\r\n
// server responds transaction ID S6, mode 0, error code 06, M/A mode mismatched while writing (suppose it Manual Mode while writing).

< $***TMSVR***,18,S7,*2*,adata={1,2,3},*47\r\n // transaction ID S7, string format, set adata={1,2,3}

> $***TMSVR***,24,S7,*0*,07,ValueError;adata,*42\r\n

// server responds transaction ID S7, mode 0, error code 07, writing values and data size or type mismatched. (the configured size is 4, but there is only 3 to write.)

17.4.2 Mode = 1 BINARY

The data content is transmitted in binary mode by converting the data item name with the Little Endian value and the value with UTF8 to a byte array accordingly. The format is shown as below.

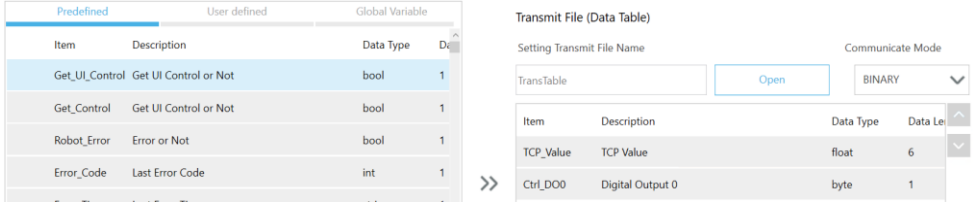
Data

ID		Mode		Content
Transaction ID	,	***1***	,	Item and Value

Length of Item *2 bytes Little Endian*	***Item*** *UTF8*	***Length of Value*** *2 bytes Little Endian*	***Value*** *Little Endian / UTF8*	...

Length of Item 2 bytes in Little Endian, value from 0 to 65535 indicating the length of the item that follows
Item item name
Length of Value 2 bytes in Little Endian), value from 0 to 65535 indicating the length of the data value that follows
Value data value

Suppose taking Check TCP_Value float[] and Ctrl_DO0 byte as the communication data and transmitting in binary mode.



> 24 54 4D 53 56 52 2C // $TMSVR, // Header
36 39 2C // 69, // Length
30 2C *31* 2C // 0,1, // transaction ID 0, mode 1, binary
0A 00 *52 6F 62 6F 74 5F 4C 69 6E 6B* 01 00 *00* // Robot_Link=0
// The name occupied 10 bytes, the value, 1 byte
09 00 *54 43 50 5F 56 61 6C 75 65* 18 00 *00 00 80 3F 00 00 80 3F 00 00 80 3F CD*

```
CC CC 3D CD CC 4C 3E CD CC CC 3D          // TCP_Value={1,1,1,0.1,0.2,0.1}
// The name occupied 9 bytes, the value, 24 bytes
08 00 43 74 72 6C 5F 44 4F 30 01 00 00    // Ctrl_DO0=0
// The name occupied 8 bytes, the value, 1 byte
2C 2A 39 36 0D 0A          // ,*96\r\n      // Checksum

<  24 54 4D 53 56 52 2C     // $TMSVR,       // Header
   31 38 2C                 // 18,           // Length
   54 31 2C 31 2C           // T1,1,         // transaction ID T1, mode 1, binary
   08 00 43 74 72 6C 5F 44 4F 30 01 00 01   // Ctrl_DO0=1
   // The name occupied 8 bytes, the value, 1 byte
   2C 2A 37 41 0D 0A        // ,*7A\r\n      // Checksum
>  $TMSVR,10,T1,0,00,OK,*1E\r\n
   // server responds to ID T1, mode 1, error code 00, correct writing
```

Once the data type of the item to send is string [], two bytes, *0x00 0x00*, are inserted between the string elements as the separators.

```
>  24 54 4D 53 56 52 2C     // $TMSVR,       // Header
   39 30 2C                 // 90,           // Length
   30 2C 31 2C              // 0,1           // transaction ID 0, mode 1, binary
   0A 00 52 6F 62 6F 74 5F 4C 69 6E 6B 01 00 00   // Robot_Link=0
   //The name occupied 10 bytes, the value, 1 byte
   09 00 54 43 50 5F 56 61 6C 75 65 18 00 00 00 80 3F 00 00 80 3F 00 00 80 3F CD
   CC CC 3D CD CC 4C 3E CD CC CC 3D       // TCP_Value={1,1,1,0.1,0.2,0.1}
   //The name occupied 9 bytes, the value, 24 bytes
   08 00 43 74 72 6C 5F 44 4F 30 01 00 01    // Ctrl_DO0=1
   // The name occupied 8 bytes, the value, 1 byte
   04 00 67 5F 73 73 0D 00 48 69 00 00 54 4D 00 00 52 6F 62 6F 74
                            // g_ss={"Hi","TM","Robot"}
                            // The name occupied 4 bytes, the value, 13 bytes
   2C 2A 44 43 0D 0A        // ,*DC\r\n      // Checksum
```

Also, if the data type of the item to receive is string [], when converting to a byte array, two bytes, 00 00, are inserted between the string elements as the separators.

```
<  24 54 4D 53 56 52 2C     // $TMSVR,       // Header
   32 35 2C                 // 25,           // Length
   54 32 2C 31 2C           // T2,1,         // transaction ID T2, mode 1, binary
   04 00 67 5F 73 73 0C 00 48 65 6C 6C 6F 00 00 57 6F 72 6C 64
                            // g_ss={"Hello", "World"}
                            // The name occupied 4 bytes, the value, 12 bytes
   2C 2A 30 32 0D 0A        // ,*02\r\n      // Checksum
>  $TMSVR,10,T2,0,00,OK,*1D\r\n
   //server responds to ID T2, mode 0, error code 00, correct writing
```

17.4.3 Mode = 2 STRING

The data content is transmitted as a string with the name and value of the data item in the Script string of an external command. The format is shown as below.

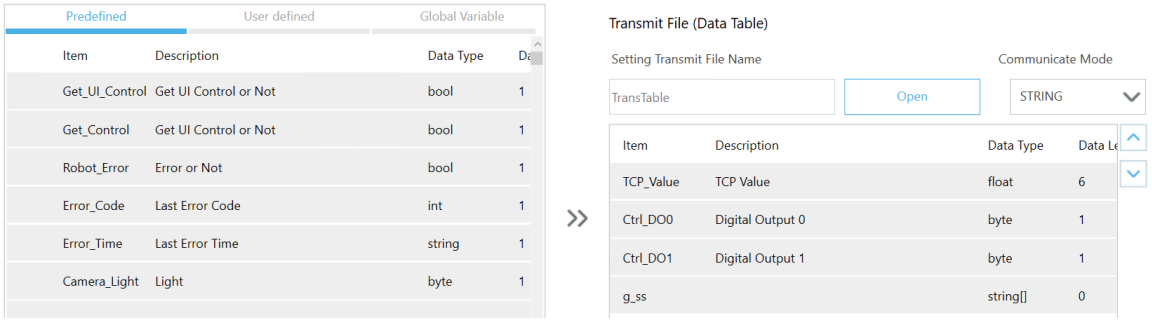
Data

ID		Mode		Content
Transaction ID	,	2	,	Item and Value

Item	=	*Value*	\r\n	...

Item item name
= equal
Value data value
\r\n symbol of carriage return as required if there is an item up next for separation.

Suppose taking Check TCP_Value float[] and Ctrl_DO0 byte, Ctrl_DO1 byte, g_ss string[] as the communication data and transmitting in string mode.



> $***TMSVR***,97,9,2,Robot_Link=0\r\n // Robot_Link=0 // transaction ID 9, mode 2, string
> TCP_Value={1,1,1,0.1,0.2,0.1}\r\n // TCP_Value={1,1,1,0.1,0.2,0.1}
> Ctrl_DO0=1\r\n // Ctrl_DO0=1
> Ctrl_DO1=0\r\n // Ctrl_DO1=0
> g_ss={"Hi","TM","Robot"},*77\r\n // g_ss={"Hi","TM","Robot"}

< $***TMSVR***,15,T2,2,Ctrl_DO0=0\r\n // set Ctrl_DO0=0 // transaction ID T2, mode 2, string
Ctrl_DO1=1,*34\r\n // set Ctrl_DO1=1
> $***TMSVR***,10,T2,0,00,OK,*1D\r\n
// server responds to ID T2, mode 0, error code 00, correct writing

17.4.4 Mode = 3 JSON

The data content is transmitted as a JSON string with the name and value of the data item serialized in the JSON format as shown below.

Data

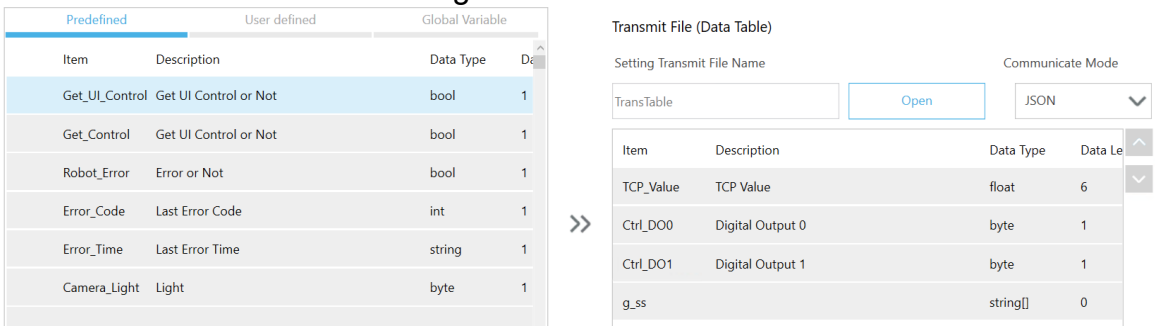
ID		Mode		Content
Transaction ID	,	3	,	Item and Value

Item item name
Value data value

```
public class TMSVRJsonData
{
    public string Item;
    public object Value;
}
```

*[] array is in use when it comes it multiple items.

Suppose taking TCP_Value float[] and Ctrl_DO0 byte, Ctrl_DO1 byte, g_ss string[] as the communication data and transmitting in JSON mode.




```
>  $TMSVR,196,5,3,[{"Item":"Robot_Link","Value":0},          // Robot_Link=0
                                                    // transaction ID 5, mode 3, JSON
   {"Item":"TCP_Value","Value":[1.0,1.0,1.0,0.1,0.2,0.1]},
   // TCP_Value={1,1,1,0.1,0.2,0.1}
   {"Item":"Ctrl_DO0","Value":0},                          // Ctrl_DO0=0
   {"Item":"Ctrl_DO1","Value":0},                          // Ctrl_DO1=0
   {"Item":"g_ss","Value":["Hi","TM","Robot"]}],*3A\r\n
   // g_ss={"Hi","TM","Robot"}

<  $TMSVR,113,T9,3,[{"Item":"Ctrl_DO0","Value":1}, // Ctrl_DO0=1
   {"Item":"Ctrl_DO1","Value":0},                          // Ctrl_DO1=0
   {"Item":"g_ss","Value":["Hello","TM","Robot"]}],*7C\r\n
   // g_ss={"Hello","TM","Robot"}
>  $TMSVR,10,T9,0,00,OK,*16\r\n
// server responds to ID T9, mode 0, error code 0, correct writing
```

17.4.5 Mode = 11 BINARY (Request read)

The data content is transmitted in binary mode by converting the data item name with the Little Endian value and the value with UTF8 to a byte array accordingly. The format is shown as below.

Data (client to server)

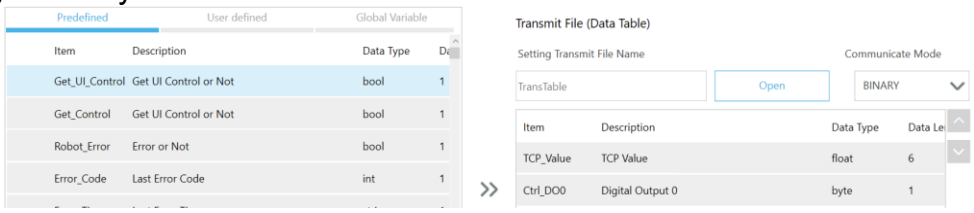
ID		Mode		Content
Transaction ID	,	***11***	,	Item

Length of Item *2 bytes Little Endian*	***Item*** *UTF8*	...

The difference of the read request from Mode = 1 is no value required.

Length of Item	2 bytes in Little Endian, value from 0 to 65535 indicating the length of the item that follows
Item	Item name

Suppose taking TCP_Value float[] and Ctrl_DO0 byte as the communication data and transmitting in binary mode.



server periodical delivery

```
>   24 54 4D 53 56 52 2C // $TMSVR,          // Header
    36 39 2C             // 69,             // Length
    30 2C 31 2C          // 0,1,            // transaction ID 0, mode 1, binary
    0A 00 52 6F 62 6F 74 5F 4C 69 6E 6B 01 00 00   // Robot_Link=0
    // The name occupied 10 bytes, the value, 1 byte
    09 00 54 43 50 5F 56 61 6C 75 65 18 00 00 00 80 3F 00 00 80 3F 00 00 80 3F CD
    CC CC 3D CD CC 4C 3E CD CC CC 3D      // TCP_Value={1,1,1,0.1,0.2,0.1}
    // The name occupied 9 bytes, the value, 24 bytes
    08 00 43 74 72 6C 5F 44 4F 30 01 00 00      // Ctrl_DO0=0
    // The name occupied 8 bytes, the value, 1 byte
    2C 2A 39 36 0D 0A    // ,*96\r\n        // Checksum
```

client requested to read

```
<   24 54 4D 53 56 52 2C     // $TMSVR,     // Header
    32 36 2C                 // 26,         // Length
    51 31 2C 31 31 2C        // Q1,11,      // transaction ID Q1, mode 11 binary (Request read)
    08 00 43 74 72 6C 5F 44 4F 30            // Ctrl_DO0     // The name occupied 8 bytes
    08 00 54 43 50 5F 4D 61 73 73            // TCP_Mass     // The name occupied 8 bytes
    2C 2A 37 46 0D 0A        // ,*7F\r\n    // Checksum
server replied with the item value
>   24 54 4D 53 56 52 2C     // $TMSVR,     // Header
```

```
      33 35 2C                    // 35,          // Length
      51 31 2C 31 31 2C           // Q1,11,       // server responds to ID Q1, mode 11 binary
      08 00 43 74 72 6C 5F 44 4F 30 01 00 00
                                  // Ctrl_DO0=0
                                  // The name occupied 8 bytes, the value, 1 byte
      08 00 54 43 50 5F 4D 61 73 73 04 00 00 00 00 00
                                  // TCP_Mass=0
                                  // The name occupied 8 bytes, the value, 4 byte
      2C 2A 37 38 0D 0A           // ,*78\r\n     // Checksum
* server replied the same content format as Mode = 1 BINARY

client requested to read
<     24 54 4D 53 56 52 2C        // $TMSVR,      // Header
      32 36 2C                    // 26,          // Length
      51 32 2C 31 31 2C           // Q2,11,       // transaction ID Q1, mode 11 binary (Request read)
      08 00 43 74 72 6C 5F 44 4F 30
                                  // Ctrl_DO0     // The name occupied 8 bytes
      08 00 54 43 50 5F 4D 61 58 58
                                  // TCP_MaXX     // The name occupied 8 bytes
      2C 2A 37 43 0D 0A           // ,*7C\r\n     // Checksum
server replied with the item value
>     $TMSVR,25,Q2,0,04,NotExist;TCP_MaXX,*17\r\n
      // server responds to ID Q2, mode 0, error code 04, item not existed
```

17.4.6 Mode = 12 STRING (Request read)

The data content is transmitted as a string with the name and value of the data item in the Script string of an external command. The format is shown as below.

Data (client to server)

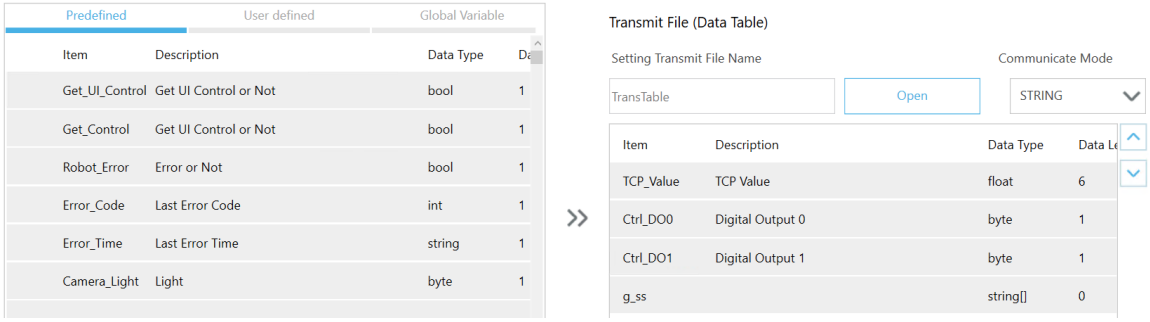
ID		Mode		Content
Transaction ID	,	12	,	Item and Value

Item	\r\n	...

No Value required.

Item	Item name
\r\n	The newline characters. Required only as a delimiter if the next item comes.

Suppose taking TCP_Value float[] and Ctrl_DO0 byte, Ctrl_DO1 byte, g_ss string[] as the communication data and transmitting in STRING mode.



server periodical delivery

```
>   $TMSVR,97,9,2,Robot_Link=0\r\n   // Robot_Link=0        // transaction ID 9, mode 2
    TCP_Value={1,1,1,0.1,0.2,0.1}\r\n   // TCP_Value={1,1,1,0.1,0.2,0.1}
    Ctrl_DO0=1\r\n                   // Ctrl_DO0=1
    Ctrl_DO1=0\r\n                   // Ctrl_DO1=0
    g_ss={"Hi","TM","Robot"},*77\r\n   // g_ss={"Hi","TM","Robot"}
```

client requested to read

```
<   $TMSVR,28,Q2,12,Robot_Link\r\n   // Item Robot_Link
                                     // transaction ID Q2, mode 12 JSON (Request read)
    TCP_Mass,*0E\r\n                 // Item TCP_Mass
```

server replied with the item value

```
>   $TMSVR,30,Q2,12,Robot_Link=0\r\n     // server responds to ID Q2, mode 12
    TCP_Mass=0,*09\r\n
```

* server replied the same content format as Mode = 2 STRING

17.4.7 Mode = 13 JSON (Request read)

The data content is transmitted as a JSON string with the name and value of the data item serialized in the JSON format as shown below.

Data (client to server)

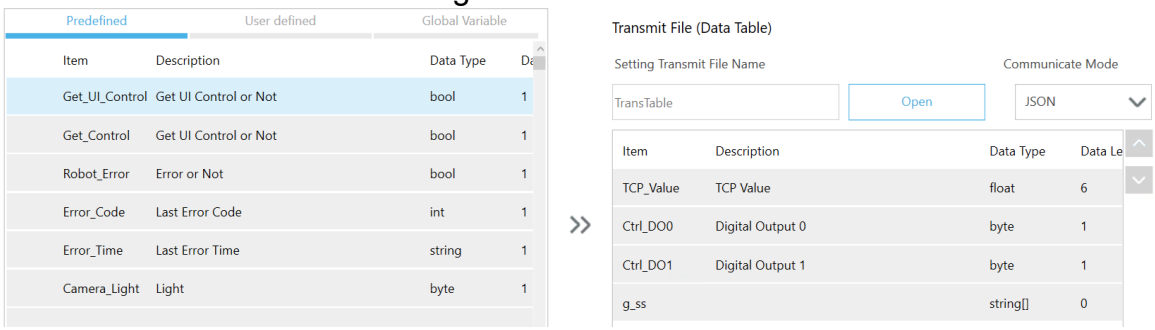
ID		Mode		Content
Transaction ID	,	13	,	Item and Value

Item Item name
Value Data value

```
public class TMSVRJsonData
{
    public string Item;
    public object Value;
}
```

* [] array is in use when it comes it multiple items.
* Shared with Mode = 3 JSON for using the same class for serialization / deserialization, but the Value attribute may not exist

Suppose taking TCP_Value float[] and Ctrl_DO0 byte, Ctrl_DO1 byte, g_ss string[] as the communication data and transmitting in JSON mode.



server periodical delivery

> $***TMSVR***,196,5,*3*,[{"Item":"Robot_Link","Value":0}, // Robot_Link=0

// transaction ID 5, mode 3

{"Item":"TCP_Value","Value":[1.0,1.0,1.0,0.1,0.2,0.1]}, // TCP_Value={1,1,1,0.1,0.2,0.1}
{"Item":"Ctrl_DO0","Value":0}, // Ctrl_DO0=0
{"Item":"Ctrl_DO1","Value":0}, // Ctrl_DO1=0
{"Item":"g_ss","Value":["Hi","TM","Robot"]}],*3A\r\n // g_ss={"Hi","TM","Robot"}

client requested to read

< $***TMSVR***,27,Q3,*13*,[{"Item":"TCP_Mass"}],*3C\r\n

// transaction ID Q3, mode 13 JSON (Request read)

server replied with the item value

> $***TMSVR***,39,Q3,*13*,[{"Item":"TCP_Mass","Value":0.0}],*40\r\n

// server responds to ID Q3, mode 13

* server replied the same content format as Mode = 3 JSON

17.5 svr_read()

Read the item value in the communication data table of Ethernet Slave in the Connection Tab of Robot Setting at the local host.

Syntax 1

? **svr_read**(
    string
)

Parameter

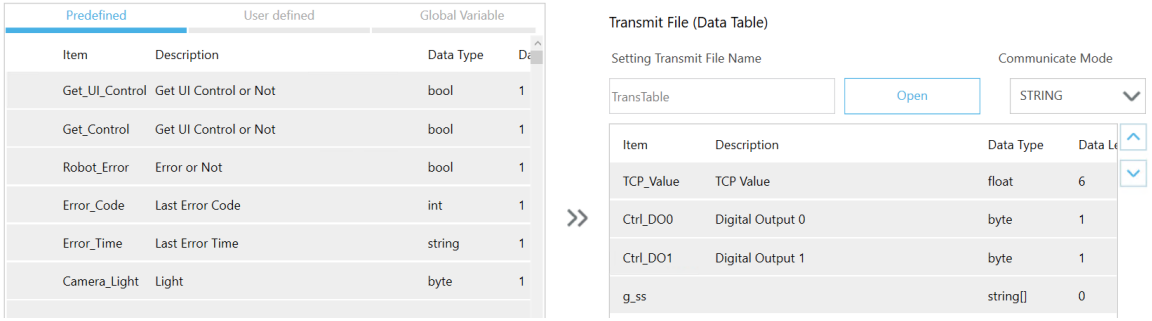
string	Item name

Return

?	Return value by set data type

Note

Suppose taking TCP_Value float[], Ctrl_DO0 byte, Ctrl_DO1 byte, and g_ss string[] as the communication data table.




```
float[] fva0= svr_read("TCP_Value")          // {1, 1, 1, 0.1, 0.2, 0.1}
byte b0 = svr_read("Ctrl_DO0")               // 0
byte b1 = svr_read("Ctrl_DO1")               // 1
string[]ss = svr_read("g_ss")          // {"Hi","TM","Robot"}
ss = g_ss                              // make the variable to take, g_ss, a variable name directly
byte st = svr_read("Robot_Link")       // 0 (Robot disconnected) 1 (Robot connected)

float[] fva1 = svr_read("TCP_Value")     // Report error. Suppose Ethernet Slave is not launched.
float[] fva2 = svr_read("TCP_Value1")    // Report error. Item name TCP_Value1 does not exist.

float[] fva3 = svr_read("g_ff")          // Report error.. Item name g_ff does not exist in the
                                         communication table.
// If g_ff is assumed to exist among the global variables, it cannot be accessed because not it does not load
all global variables.
float[] fva4 = svr_read("Coord_Base_Flange")     // {0.01,-252.6,891.7,90,0,0}
// Although added as the communication data, it's accessible for item name Coord_Base_Flange is in the
system definitions.
```

17.6 svr_write()

Write the item value into the communication data table of Ethernet Slave in the Connection Tab of Robot Setting at the local host.

Syntax 1

```
bool svr_write(
    string,
    ?
)
```

Parameters

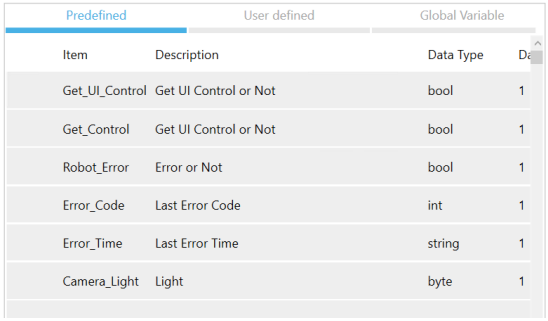
string	Item name	
?	Item value	

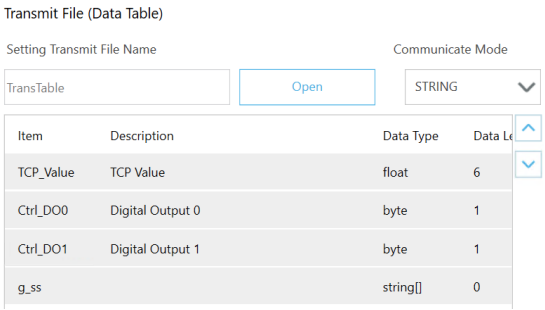
Return

bool	True	Write successfully	
	False	Write failed	Possible causes 1. Item name does not exist. 2. Unable to write the read-only item name. 3. Item value to write mismatched with item data type.

Note

Suppose taking TCP_Value float[], Ctrl_DO0 byte, Ctrl_DO1 byte, and g_ss string[] in the communication data table.






```
float[] tvalue = {1,2,3,0.1,0.2,0.3}
bool flag = false
flag = svr_write("TCP_Value", tvalue)   // flag = false    read-only, invalid process (not an error)
flag = svr_write("Ctrl_DO0", 1)         // flag = true，Ctrl_DO0 = 1
flag = svr_write("Ctrl_DO1", 0)         // flag = true，Ctrl_DO1 = 0

flag = svr_write("TCP_Value", tvalue)   // Error. Suppose Ethernet Slave is not launched.
flag = svr_write("TCP_Value1", tvalue)  // Error. Item name TCP_Value1 does not exist.
flag = svr_write("Ctrl_DO0", "True")    // Error. Item name Ctrl_DO0 writes value as string (the
                                        data type is set to byte)
```

18. Profinet Functions

The robot communicates with external controllers via the Profinet communication protocol. In the mechanism of the Profinet communication protocol, the robot works as a Profinet IO device for external devices to read and write the robot data. Meanwhile, TMflow monitors the table of data receiving from external devices and the table of data sending to external devices with Profinet functions as well as changes the custom definition section in the table of data sending to external devices.

Communication Data Table

The data table is composed of the input data and the output data. Input Data Table is for external devices posting on the robot, and Output Data Table is for the robot sending to external devices. Both of the data tables come with System Definition Section and Custom Definition Section for data.

1. System Definition Section: Items and settings are defined by the robot, and the data contents are updated by the robot or external devices. The defined items are robot status relevant such as robot bases, project status, control box status, or input/output status relevant such as digital I/Os and analog I/Os. Users can use Profinet functions to read the input data table and the output data table in the system definition section.
2. Custom Definition Section: Items and settings are defined by users, and the data contents are updated by users or external devices. In the meantime of the project editing, users can use Profinet functions to read and write the output data table in the custom definition section or read input data table in the custom definition section as well as use the custom definition section as a data exchange register between the project and external devices.

Communication Data Table (at the robot's viewpoint)	Data Section	TMflow Profinet Function Permissions	External Device Permissions
Input Data Table	System Definition Section	Read	Write
	Custom Definition Section	Read	Write
Output Data Table	System Definition Section	Read	Read
	Custom Definition Section	Read/Write	Read

18.1 profinet_read_input()

Read the input table content.

Syntax 1

```
byte[] profinet_read_input(
    int,
    int
)
```

Parameters

int	Starting address
int	The address amount to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = profinet_read_input(148,16)
    // {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
```

Syntax 2

```
byte profinet_read_input(
    int,
)
```

Parameters

int	Starting address

Return

byte	Return data in byte.

Note

```
byte var_b = profinet_read_input(148)
    // 0x30
```

Syntax 3

```
? profinet_read_input(
    string,
    int,
    int
)
```

Parameters

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

```
? profinet_read_input(
    string,
    int,
```

)

Parameters

string Item name

int The starting shifted address of the item

Return

? The data type returned by the item definition in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **profinet_read_input**(

string

)

Parameter

string Item name

Return

? The data type returned by the item definition in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = profinet_read_input("StickStatus",0,1)
    // 0x02
var_b = profinet_read_input("StickStatus",0)
    // 0x02
var_b = profinet_read_input("StickStatus")
    // 0x02
byte[] var_ba = profinet_read_input("CtrlBox_DO",0,2)
    // {0x00,0x04}
var_ba = profinet_read_input("CtrlBox_DO")
    // {0x00,0x04}
int[] var_ia = profinet_read_input("Register_Int",0,12)
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03} (Little Endian)
    to int[]
    // int[] = {0x00000001,0x00000002,0x00000003} (Little Endian)
    // int[] = {1,2,3}
var_ia = profinet_read_input("Register_Int",12)
    // byte[] = {0x00,0x00,0x00,0x04,0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,
        0x00,0x00,0x00,0x08,0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,
        0x00,0x00,0x00,0x0C,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
```

```
    // int[] = {0x00000004,0x00000005,0x00000006,0x00000007,0x00000008,0x00000009,
          0x0000000A,0x0000000B,0x0000000C,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {4,5,6,7,8,9,10,11,12,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
var_ia = profinet_read_input("Register_Int")
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03,0x00,0x00,0x00,0x04,
          0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,0x00,0x00,0x00,0x08,
          0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,0x00,0x00,0x00,0x0C,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)          to int[]
    // int[] = {0x00000001,0x00000002,0x00000003,0x00000004,0x00000005,0x00000006,
          0x00000007,0x00000008,0x00000009,0x0000000A,0x0000000B,0x0000000C,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {1,2,3,4,5,6,7,8,9,10,11,12,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
float[] var_fa = profinet_read_input("Register_Float",4,12)
    // byte[] = {0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66} (Big Endian)  to float[]
    // float[] = {0x3F99999A,0x3FA66666,0x40066666} (Big Endian)
    // float[] = {1.2,1.3,2.1}
var_fa = profinet_read_input("Register_Float",12)
    // byte[] = {0x40,0x06,0x66,0x66,0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Big Endian)    to float[]
    // float[] = {0x40066666,0x400CCCCD,0x40133333,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
          0x00000000,0x00000000,0x00000000} (Big Endian)
    // float[] = {2.1,2.2,2.3,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
var_fa = profinet_read_input("Register_Float")
    // byte[] = {0x3F,0x8C,0xCC,0xCD,0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66,
          0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Big Endian)    to float[]
```

```
// float[] = {0x3F8CCCCD,0x3F99999A,0x3FA66666,0x40066666,0x400CCCCD,0x40133333,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000} (Big Endian)
// float[] = {1.1,1.2,1.3,2.1,2.2,2.3,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
```

18.2 profinet_read_input_int()

Read the input table content and convert the data to the 32-bit integer.

Syntax 1

int[] **profinet_read_input_int**(
int,
int,
int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **profinet_read_input_int**(
int,
int
)

Parameters

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
* Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = profinet_read_input_int(164,12,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}

    var_ia = profinet_read_input_int(164,11,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF} (Little Endian)      to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
    // int[] = {32767,99999,16744448}

    var_ia = profinet_read_input_int(164,10,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80} (Little Endian)to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00008000} (Little Endian)
    // int[] = {32767,99999,32768}
```

```
var_ia = profinet_read_input_int(164,12,1)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Big Endian)  to int[]
    // int[] = {0xFF7F0000,0x9F860100,0x0080FFFF} (Big Endian)
    // int[] = {-8454144,-1618607872,8454143}

var_ia = profinet_read_input_int(164,12,2)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}

var_ia = profinet_read_input_int(164,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
```

Syntax 3

```
int profinet_read_input_int(
    int
)
```

Parameters

int	Starting address * Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = profinet_read_input_int(164)
    // byte[] = {0xE4,0x07,0x00,0x00} (Little Endian)  to int
    // int = 0x000007E4 (Little Endian)
    // int = 2020
var_i = profinet_read_input_int(164)
    // byte[] = {0x00,0x00,0x07,0xE4} (Big Endian)          to int
    // int = 0x000007E4 (Big Endian)
    // int = 2020
```

18.3 profinet_read_input_float()

Read the input table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **profinet_read_input_float**(
int,
int,
int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **profinet_read_input_float**(
int,
int
)

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
* Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = profinet_read_input_float(284,12,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}
var_fa = profinet_read_input_float(284,11,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00400000} (Little Endian)
    // float[] = {1.0,2.0,5.877472E-39}
var_fa = profinet_read_input_float(284,10,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00000000} (Little Endian)
    // float[] = {1.0,2.0,0.0}

var_fa = profinet_read_input_float(284,12,1)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
```

```
        // float[] = {0x0000803F,0x00000040,0x00004040} (Big Endian)
        // float[] = {4.600603E-41,8.96831E-44,2.304856E-41}

    var_fa = profinet_read_input_float(284,12,2)
        // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
        to float[]
        // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
        // float[] = {1.0,2.0,3.0}

    var_fa = profinet_read_input_float(284,12)
        // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
        to float[]
        // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
        // float[] = {1.0,2.0,3.0}
```

Syntax 3

```
float profinet_read_input_float(
    int
)
```

Parameters

int	Starting address * Convert the read data to a floating-point number based on Little Endian (DCBA) or Big Endian (ABCD).

Return

float	Return data in floating-point number.

Note

```
    float var_f = profinet_read_input_float(284)
        // byte[] = {0x00,0x00,0x80,0x3F} (Little Endian) to float
        // float = 0x3F800000 (Little Endian)
        // float = 1.0
    var_f = profinet_read_input_float(284)
        // byte[] = {0x3F,0x80,0x00,0x00} (Big Endian) to float
        // float = {0x3F800000} (Big Endian)
        // float = {1.0}
```

18.4 profinet_read_input_string()

Read the input table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string profinet_read_input_string(
    int,
    int
)
```

Parameters

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = profinet_read_input_string(148,16)
    // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "TM5-700"
var_s = profinet_read_input_string(148,32)
    // byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "01060112"
var_s = profinet_read_input_string(148,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                 0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明機器人 1234"
var_s = profinet_read_input_string(148,10)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E}
    // string = "abcd 達明"
var_s = profinet_read_input_string(148,8)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6}
    // string = "abcd 達"
```

18.5 profinet_read_input_bit()

Read the input table content and retrieve the nth bit value of the data byte.

Syntax 1

byte **profinet_read_input_bit**(
int,
int
)

Parameters

int	Starting address
int	The nth bit value in the data byte

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0.

Note

```
byte var_b = profinet_read_input_bit(148,0)
    // 0x30     get bit: "0"
    // 0
var_b = profinet_read_input_bit(148,5)
    // 0x30     get bit: "5"
    // 1
```

Syntax 2

byte **profinet_read_input_bit**(
string,
int
)

Parameters

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = profinet_read_input_bit("Register_Bit",0)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // 1    get bit: "0"
var_b = profinet_read_input_bit("Register_Bit",17)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // 0    get bit: "17"
```

Syntax 3

byte[] **profinet_read_input_bit**(
int,

int,
int
)
Parameters
int Starting address
int Starting bit
int The amount of bit to read
Return
byte[] Return data in byte[].
Return 1 for bit value == 1.
Return 0 for bit value == 0.
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
Note
byte[] var_ba = **profinet_read_input_bit**(148,0,20)
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…} // total
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = **profinet_read_input_bit**(148,12,8)
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…} // total
// byte[] = {1,1,0,1,0,0,1,1}

Syntax 4

byte[] **profinet_read_input_bit**(
string,
int,
int
)
Parameters
string Item name
int Starting bit
int he amount of bit to read
Return
byte[] Return data in byte[].
Return 1 for bit value == 1.
Return 0 for bit value == 0.
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
Note
byte[] var_ba = **profinet_read_input_bit**("Register_Bit",0,20)
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…} // total
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = **profinet_read_input_bit**("Register_Bit",12,8)
// byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…} // total
// byte[] = {1,1,0,1,0,0,1,1}

18.6 profinet_read_output()

Read the output table content.

Syntax 1

```
byte[] profinet_read_output(
    int,
    int
)
```

Parameters

int	Starting address
int	The address length to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = profinet_read_output(540,16)
    // {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
```

Syntax 2

```
byte profinet_read_output(
    int
)
```

Parameters

int	Starting address

Return

byte	Return data in byte

Note

```
byte var_b = profinet_read_output(540)
    // 0x30
```

Syntax 3

```
? profinet_read_output(
    string,
    int,
    int
)
```

Parameters

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

```
? profinet_read_output(
    string,
    int,
)
```

Parameters

string	Item name
int	The starting shifted address of the item

Return

? The data type returned by the item defined in the communication data table.
* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **profinet_read_output**(
string
)

Parameter

string	Item name

Return

? The data type returned by the item defined in the communication data table.
* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = profinet_read_output("ManualAuto",0,1)
    // 0x02
var_b = profinet_read_output("ManualAuto",0)
    // 0x02
var_b = profinet_read_output("ManualAuto")
    // 0x02

byte[] var_ba = profinet_read_output("Error_Code",0,4)
    // {0x00,0x04,0x80,0x0C}
var_ba = profinet_read_output("Error_Code",0,2)
    // {0x00,0x04}
var_ba = profinet_read_output("Error_Code")
    // {0x00,0x04,0x80,0x0C}

var_int i = profinet_read_output("Current_Time_YY")
    // byte[] = {0x00,0x00,0x07,0xE4} (Little Endian)  to int
    // int = 0x000007E4 (Little Endian)
    // int = 2020

int[] var_ia = profinet_read_output("Register_Int",0,12)
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03} (Little Endian)
    to int[]
    // int[] = { 0x00000001,0x00000002,0x00000003} (Little Endian)
    // int[] = {1,2,3}
```

```
var_ia = profinet_read_output("Register_Int",12)
    // byte[] = {0x00,0x00,0x00,0x04,0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,
        0x00,0x00,0x00,0x08,0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,
        0x00,0x00,0x00,0x0C,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00000004,0x00000005,0x00000006,0x00000007,0x00000008,0x00000009,
        0x0000000A,0x0000000B,0x0000000C,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {4,5,6,7,8,9,10,11,12,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}
var_ia = profinet_read_output("Register_Int")
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03,0x00,0x00,0x00,0x04,
        0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,0x00,0x00,0x00,0x08,
        0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,0x00,0x00,0x00,0x0C,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)          to int[]
    // int[] = {0x00000001,0x00000002,0x00000003,0x00000004,0x00000005,0x00000006,
        0x00000007,0x00000008,0x00000009,0x0000000A,0x0000000B,0x0000000C,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {1,2,3,4,5,6,7,8,9,10,11,12,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0}

float var_f = profinet_read_output("Current_TCP_Mass")
    // byte[] = {0x40,0x40,0x00,0x00} (Big Endian)          to float
    // float = 0x40400000 (Big Endian)
    // float = 3.0

var_fa = profinet_read_output("Current_TCP_Value",4,12)
    // byte[] = {0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66} (Big Endian)  to float[]
    // float[] = {0x3F99999A,0x3FA66666,0x40066666} (Big Endian)
    // float[] = {1.2,1.3,2.1}
var_fa = profinet_read_output("Current_TCP_Value",12)
    // byte[] = { 0x40,0x06,0x66,0x66,0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33} (Big Endian)
    to float[]
    // float[] = {0x40066666,0x400CCCCD,0x40133333} (Big Endian)
    // float[] = {2.1,2.2,2.3}
var_fa = profinet_read_output("Current_TCP_Value")
    // byte[] = {0x3F,0x8C,0xCC,0xCD,0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66,
        0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33} (Big Endian) to float[]
    // float[] = {0x3F8CCCCD,0x3F99999A,0x3FA66666,0x40066666,0x400CCCCD,0x40133333}
```

```
        (Big Endian)
        // float[] = { 1.1,1.2,1.3,2.1,2.2,2.3}

string var_s = profinet_read_output ("RobotModel",0,16)
        // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        // string = "TM5-700"
var_s = profinet_read_output ("RobotModel",4,3)
        // byte[] = {0x37,0x30,0x30}
        // string = "700"
var_s = profinet_read_output ("RobotModel")
        // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        // string = "TM5-700"
```

18.7 profinet_read_output_int()

Read the output table content and convert the data to the 32-bit integer.

Syntax 1

int[] **profinet_read_output_int**(
int,
int,
int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **profinet_read_output_int**(
int,
int
)

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = profinet_read_output_int(556,12,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
var_ia = profinet_read_output_int(556,11,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF} (Little Endian)      to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
    // int[] = {32767,99999,16744448}
var_ia = profinet_read_output_int(556,10,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80} (Little Endian)to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00008000} (Little Endian)
    // int[] = {32767,99999,32768}

var_ia = profinet_read_output_int(556,12,1)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0xFF7F0000,0x9F860100,0x0080FFFF} (Big Endian)
```

```
        // int[] = {-8454144,-1618607872,8454143}

    var_ia = profinet_read_output_int(556,12,2)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}

    var_ia = profinet_read_output_int(556,12)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}
```

Syntax 3

```
int profinet_read_output_int(
    int
)
```

Parameters

int	Starting address * Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
    int var_i = profinet_read_output_int(556)
        // byte[] = {0xE4,0x07,0x00,0x00} (Little Endian)  to int
        // int = 0x000007E4 (Little Endian)
        // int = 2020
    var_i = profinet_read_output_int(556)
        // byte[] = {0x00,0x00,0x07,0xE4} (Big Endian)    to int
        // int = 0x000007E4 (Big Endian)
        // int = 2020
```

18.8 profinet_read_output_float()

Read the output table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **profinet_read_output_float**(
int,
int,
int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **profinet_read_output_float**(
int,
int
)

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = profinet_read_output_float(676,12,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}
var_fa = profinet_read_output_float(676,11,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00400000} (Little Endian)
    // float[] = {1.0,2.0,5.877472E-39}
var_fa = profinet_read_output_float(676,10,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00000000} (Little Endian)
    // float[] = {1.0,2.0,0.0}

var_fa = profinet_read_output_float(676,12,1)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
```

```
        to float[]
        // float[] = {0x0000803F,0x00000040,0x00004040} (Big Endian)
        // float[] = {4.600603E-41,8.96831E-44,2.304856E-41}

    var_fa = profinet_read_output_float(676,12,2)
        // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
        to float[]
        // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
        // float[] = {1.0,2.0,3.0}

    var_fa = profinet_read_output_float(676,12)
        // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
        to float[]
        // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
        // float[] = {1.0,2.0,3.0}
```

Syntax 3

```
float profinet_read_output_float(
    int
)
```

Parameters

int	Starting address * Convert the read data to a floating-point number based on Little Endian (DCBA) or Big Endian (ABCD).

Return

float	Return data in a floating-point number.

Note

```
    float var_f = profinet_read_output_float(676)
        // byte[] = {0x00,0x00,0x80,0x3F} (Little Endian) to float
        // float = 0x3F800000 (Little Endian)
        // float = 1.0
    var_f = profinet_read_output_float(676)
        // byte[] = {0x3F,0x80,0x00,0x00} (Big Endian) to float
        // float = 0x3F800000 (Big Endian)
        // float = 1.0
```

18.9 profinet_read_output_string()

Read the output table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string profinet_read_output_string(
    int,
    int
)
```

Parameters

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = profinet_read_output_string(540,16)
    // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "TM5-700"

var_s = profinet_read_output_string(540,32)
    // byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "01060112"

var_s = profinet_read_output_string(540,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                 0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明機器人 1234"
var_s = profinet_read_output_string(540,10)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E}
    // string = "abcd 達明"
var_s = profinet_read_output_string(540,8)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6}
    // string = "abcd 達"
```

18.10 profinet_read_output_bit()

Read the output table content and retrieve the nth bit value of the data byte.

Syntax 1

byte **profinet_read_output_bit**(
int,
int
)

Parameters

int	Starting address
int	The nth bit value in the data byte

Return

Byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0.

Note

```
byte var_b = profinet_read_output_bit(540,0)
    // 0x30     get bit: "0"
    // 0
var_b = profinet_read_output_bit(540,5)
    // 0x30     get bit: "5"
    // 1
```

Syntax 2

byte **profinet_read_output_bit**(
string,
int
)

Parameters

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte[] var_data = {57,184,12}
profinet_write_output(540,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte var_b = profinet_read_output_bit("Register_Bit",0)
    // 1
var_b = profinet_read_output_bit("Register_Bit",17)
    // 0
```

Syntax 3

byte[] **profinet_read_output_bit**(
int,

```
    int,
    int
)
```
Parameters

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_data = {57,184,12}
profinet_write_output(540,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte[] var_ba = profinet_read_output_bit(540,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = profinet_read_output_bit(540,12,8)
    // byte[] = {1,1,0,1,0,0,1,1}
```

Syntax 4

```
byte[] profinet_read_output_bit(
    string,
    int,
    int
)
```
Parameters

string	Item name
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_data = {57,184,12}
profinet_write_output(540,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte[] var_ba = profinet_read_output_bit("Register_Bit",0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = profinet_read_output_bit("Register_Bit",12,8)
    // byte[] = {1,1,0,1,0,0,1,1}
```

18.11 profinet_write_output()

Write data to the output table.

Syntax 1

bool **profinet_write_output** (
int,
?,
int
)

Parameters

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	The maximum amount of the address to write	
	> 0	Legitimate data length. Write by the amount of the address.
	<= 0	Illegitimate data length. Write by the complete length of the data to write.

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 2

bool **profinet_write_output**(
int,
?
)

Parameters

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	

Return

Bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 1. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 3

bool **profinet_write_output**(
int,
?,
int,

int
)

Parameters

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	Starting address of the data to write	
int	The amount of the address to write	

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
byte var_data = 255
profinet_write_output(540,var_data,1)
byte var_b = profinet_read_output(540)
    // 0xFF

byte[] var_data = {1,127,255}
profinet_write_output(540,var_data,3)
byte[] var_ba = profinet_read_output(540,3)
    // {0x01,0x7F,0xFF}
profinet_write_output(540,var_data,2)
var_ba = profinet_read_output(540,3)
    // {0x01,0x7F,0x00}
profinet_write_output(540,var_data,-1)
var_ba = profinet_read_output(540,3)
    // {0x00,0x7F,0xFF}

int var_data = 32767
profinet_write_output(556,var_data,4)
int var_i = profinet_read_output_int(556)
    // byte[] = {0xFF,0x7F,0x00,0x00} (Little Endian)  to int
    // int = 0x00007FFF (Little Endian)
    // int = 32767
profinet_write_output(556,var_data,1)
var_i = profinet_read_output_int(556)
    // byte[] = {0xFF,0x00,0x00,0x00} (Little Endian)  to int
    // int = 0x000000FF (Little Endian)
    // int = 255

int[] var_data = {32767,99999,-32768}
profinet_write_output(556,var_data,12)
int[] var_ia = profinet_read_output_int(556,12)
```

```
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}
profinet_write_output(556,var_data,3)
var_ia = profinet_read_output_int(556,12)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x00000000,0x00000000} (Little Endian)
        // int[] = {32767,0,0}
profinet_write_output(556,var_data,11)
var_ia = profinet_read_output_int(556,12)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0x00} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
        // int[] = {32767,99999,16744448}
profinet_write_output(556,var_data,4,4)
var_ia = profinet_read_output_int(556,12)
        // byte[] = {0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
        to int[]
        // int[] = {0x0001869F,0x00000000,0x00000000} (Little Endian)
        // int[] = {99999,0,0}

float var_data = -10.0
profinet_write_output(676,var_data,4)
float var_f = profinet_read_output_float(676)
        // byte[] = {0x00,0x00,0x20,0xC1} (Little Endian)  to float
        // float = 0xC1200000 (Little Endian)
        // float = -10.0
profinet_write_output(676,var_data,1)
var_f = profinet_read_output_float(676)
        // byte[] = {0x00,0x00,0x00,0x00} (Little Endian)  to float
        // float = 0x00000000 (Little Endian)
        // float = 0

float[] var_data = {-10.0,3.3,123.45}
profinet_write_output(676,var_data,12)
float[] var_fa = profinet_read_output_float(676,12)
        // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
        to float[]
        // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
        // float[] = {-10,3.3,123.45}
profinet_write_output(676,var_data,3)
var_fa = profinet_read_output_float(676,12)
        // byte[] = {0x00,0x00,0x20,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
        to float[]
        // float[] = {0x00200000,0x00000000,0x00000000} (Little Endian)
        // float[] = {2.938736E-39,0,0}
```

```
profinet_write_output(676,var_data,11)
var_fa = profinet_read_output_float(676,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x00} (Little Endian)
    to float[]
    // float[] = {0xC1200000,0x40533333,0x00F6E666} (Little Endian)
    // float[] = {-10,3.3,2.267418E-38}
profinet_write_output(676,var_data,4,4)
var_fa = profinet_read_output_float(676,12)
    // byte[] = {0x33,0x33,0x53,0x40,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to float[]
    // float[] = {0x40533333,0x00000000,0x00000000} (Little Endian)
    // float[] = {3.3,0,0}

string var_data = "abcd 達明機器人 1234"
profinet_write_output(540,var_data,32)
string var_s = profinet_read_output_string(540,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                 0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明機器人 1234"
profinet_write_output(540,var_data,10)
var_s = profinet_read_output_string(540,32)
    // byte[] = { 0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明"
profinet_write_output(540,var_data,8)
var_s = profinet_read_output_string(540,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達"
profinet_write_output(540,var_data,4,15)
var_s = profinet_read_output_string(540,15)
    // byte[] = {0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
    // string = "達明機器人"
```

Syntax 4

```
bool profinet_write_output(
    string,
    int,
    ?
    int,
    int
)
```

Parameters

string	Item name
int	The starting shifted address of the item
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**
int	Starting address of the data to write

int The amount of the address to write

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 5

```
bool profinet_write_output(
    string,
    int,
    ?
    int
)
```

Parameters

string Item name

int The starting shifted address of the item

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

int Starting address of the data to write

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 6

```
bool profinet_write_output(
    string,
    int,
    ?
)
```

Parameters

string Item name

int The starting shifted address of the item

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting address to write and write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 7

bool **profinet_write_output**(
string,
?
)

Parameters

string	Item name	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting shifted address and the starting address to write as well as write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
int[] var_data = {32767,99999,-32768}
profinet_write_output("Register_Int",0,var_data,0,12)
int[] var_ia = profinet_read_output_int(556,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
profinet_write_output("Register_Int",4,var_data,4,4)
var_ia = profinet_read_output_int(556,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to int[]
    // int[] = {0x00000000,0x0001869F,0x00000000} (Little Endian)
    // int[] = {0,99999,0}
profinet_write_output("Register_Int",4,var_data)
var_ia = profinet_read_output_int(556,20)
    // byte[] = {0x00,0x00,0x00,0x00,0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF,
        0x00,0x00,0x00,0x00} (Little Endian)  to int[]
    // int[] = {0x00000000,0x00007FFF,0x0001869F,0xFFFF8000,0x00000000} (Little Endian)
    // int[] = {0,32767,99999,-32768,0}

float[] var_data = {-10.0,3.3,123.45}
```

```
profinet_write_output("Register_Float",0,var_data,0,12)
float[] var_fa = profinet_read_output_float(676,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
    to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10,3.3,123.45}
profinet_write_output("Register_Float",4,var_data,4,8)
var_fa = profinet_read_output_float(676,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
    to float[]
    // float[] = {0x00000000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,3.3,123.45}
profinet_write_output("Register_Float",8,var_data)
var_fa = profinet_read_output_float(676,20)
    // byte[] = {0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,
        0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0x00000000,0x00000000,0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,0,-10,3.3,123.45}
```

18.12 profinet_write_output_bit()

Write content to the nth bit value of the data byte in the output table.

Syntax 1

bool **profinet_write_output_bit**(
int,
int,
int
)

Parameters

int	Starting address	
int	The nth bit value in the data byte	
int	The data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
profinet_write_output(540,var_data)
byte var_b = profinet_read_output(540)
    // 0xF0
profinet_write_output_bit(540,1,1)
var_b = profinet_read_output_bit(540,1)
    // 0xF2     get bit: "1"
    // 1
profinet_write_output_bit(540,7,0)
var_b = profinet_read_output_bit(540,7)
    // 0x72     get bit: "7"
    // 0
```

Syntax 2

bool **profient_write_output_bit**(
string,
int,
int
)

Parameter

int	Item name
int	The nth bit value
int	The data to write
	*Data in bit will write in int.

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
profinet _write_output(540,var_data)
```

```
byte var_b = profinet _read_output(540)
    // 0xF0
profinet _write_output_bit("Register_Bit",1,1)
var_b = profinet _read_output_bit(540,1)
    // 0xF2     get bit: "1"
    // 1
profinet _write_output_bit("Register_Bit",7,0)
var_b = profinet _read_output_bit(540,7)
    // 0x72     get bit: "7"
    // 0
```

Syntax 3

```
bool profinet_write_output_bit(
    int,
    int,
    byte[],
    int,
    int
)
```

Parameters

int	Starting address
int	Starting bit
byte[]	Data to write. *Data in bit will write in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int	Starting bit to write data
int	The amount of bit to write data

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 4

```
bool profinet_write_output_bit(
    int,
    int,
    byte[],
    int
)
```

Parameters

int	Starting address
int	The nth bit value
byte[]	The data to write *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int	The starting bit of the data to write

Return

bool	True	Write successfully.

	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

*Same as syntax 3. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 5

bool **profinet_write_output_bit**(
int,
int,
byte[]
)

Parameters

int	Starting address
int	The nth bit value
byte[]	The data to write *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

*Same as syntax 3. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
profinet_write_output_bit(540,0,var_data,0,20)
byte[] var_ba = profinet_read_output (540,0,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = profinet_read_output_bit(540,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
profinet_write_output_bit(540,3,var_data,5,10)
var_ba = profinet_read_output (540,0,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = profinet_read_output_bit(540,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

Syntax 6

bool **profinet_write_output_bit**(
string,
int,
byte[],
int,
int
)

Parameters

string	Item name
int	Starting bit

byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int The starting bit to write data
int The bit amount of the data to write

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 7

bool **profinet_write_output_bit**(
string,
int,
byte[],
int
)

Parameters

string Item name
int Starting bit
byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int The starting bit to write data

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

*Same as syntax 6. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 8

bool **profinet_write_output_bit**(
string,
int,
byte[]
)

Parameters

string Item name
int Starting bit
byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

*Same as syntax 6. Fill 0 as the starting bit to write as well as write with the full length of

the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
profinet_write_output_bit("Register_Bit",0,var_data,0,20)
byte[] var_ba = profinet_read_output (540,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = profinet_read_output_bit(540,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
profinet_write_output_bit("Register_Bit",3,var_data,5,10)
var_ba = profinet_read_output (540,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = profinet_read_output_bit(540,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

19. EtherNet/IP Functions

The robot communicates with external controllers via the EtherNet/IP communication protocol. In the mechanism of the EtherNet/IP communication protocol, the robot works as an EtherNet/IP IO device for external devices to read and write the robot data. Meanwhile, TMflow monitors the table of data receiving from external devices and the table of data sending to external devices with EtherNet/IP functions as well as changes the custom definition section in the table of data sending to external devices.

Communication Data Table

The data table is composed of the input data and the output data. Input Data Table is for external devices posting on the robot, and Output Data Table is for the robot sending to external devices. Both of the data tables come with System Definition Section and Custom Definition Section for data.

1. System Definition Section: Items and settings are defined by the robot, and the data contents are updated by the robot or external devices. The defined items are robot status relevant such as robot bases, project status, control box status, or input/output status relevant such as digital I/Os and analog I/Os. Users can use EtherNet/IP functions to read the input data table and the output data table in the system definition section.
2. Custom Definition Section: Items and settings are defined by users, and the data contents are updated by users or external devices. In the meantime of the project editing, users can use EtherNet/IP functions to read and write the output data table in the custom definition section or read input data table in the custom definition section as well as use the custom definition section as a data exchange register between the project and external devices.

Communication Data Table (at the robot's viewpoint)	Data Section	TMflow EtherNet/IP Function Permissions	External Device Permissions
Input Data Table	System Definition Section	Read	Write
	Custom Definition Section	Read	Write
Output Data Table	System Definition Section	Read	Read
	Custom Definition Section	Read/Write	Read

19.1 eip_read_input()

Read the input table content.

Syntax 1

byte[] **eip_read_input**(
int,
int
)

Parameters

int	Starting address
int	The address amount to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = eip_read_input(104,8)
    // {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32}
```

Syntax 2

byte **eip_read_input**(
int,
)

Parameters

int	Starting address

Return

byte	Return data in byte.

Note

```
byte var_b = eip_read_input(104)
    // 0x30
```

Syntax 3

? **eip_read_input**(
string,
int,
int
)

Parameters

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **eip_read_input**(
string,
int,

)

Parameters

string Item name

int The starting shifted address of the item

Return

? The data type returned by the item definition in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **eip_read_input**(

string

)

Parameters

string Item name

Return

? The data type returned by the item definition in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = eip_read_input("O2T_StickStatus",0,1)
    // 0x02
var_b = eip_read_input("O2T_StickStatus",0)
    // 0x02
var_b = eip_read_input("O2T_StickStatus")
    // 0x02

byte[] var_ba = eip_read_input("O2T_CtrlBox_DO",0,2)
    // {0x00,0x04}
var_ba = eip_read_input("O2T_CtrlBox_DO")
    // {0x00,0x04}
int[] var_ia = eip_read_input("O2T_Register_Int",0,12)
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03} (Little Endian) to int[]
    // int[] = {0x00000001,0x00000002,0x00000003} (Little Endian)
    // int[] = {1,2,3}

var_ia = eip_read_input("O2T_Register_Int",12)
    // byte[] = {0x00,0x00,0x00,0x04,0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,
        0x00,0x00,0x00,0x08,0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,
        0x00,0x00,0x00,0x0C,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}  (Little
        Endian) to int[]
    // int[] = {0x00000004,0x00000005,0x00000006,0x00000007,0x00000008,0x00000009,
        0x0000000A,0x0000000B,0x0000000C,0x00000000,0x00000000,0x00000000} (Little Endian)
```

```
    // int[] = {4,5,6,7,8,9,10,11,12,0,0,0}

var_ia = eip_read_input("O2T_Register_Int")
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03,0x00,0x00,0x00,0x04,
        0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,0x00,0x00,0x00,0x08,
        0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,0x00,0x00,0x00,0x0C,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00000001,0x00000002,0x00000003,0x00000004,0x00000005,0x00000006,
        0x00000007,0x00000008,0x00000009,0x0000000A,0x0000000B,0x0000000C,
        0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {1,2,3,4,5,6,7,8,9,10,11,12,0,0,0}
float[] var_fa = eip_read_input("O2T_Register_Float",4,12)
    // byte[] = {0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66} (Big Endian)  to float[]
    // float[] = {0x3F99999A,0x3FA66666,0x40066666} (Big Endian)
    // float[] = {1.2,1.3,2.1}

var_fa = eip_read_input("O2T_Register_Float",12)
    // byte[] = {0x40,0x06,0x66,0x66,0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        (Big Endian)      to float[]
    // float[] = {0x40066666,0x400CCCCD,0x40133333,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000} (Big Endian)
    // float[] = {2.1,2.2,2.3,0,0,0,0,0,0,0,0,0}

var_fa = eip_read_input("O2T_Register_Float")
    // byte[] = {0x3F,0x8C,0xCC,0xCD,0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66,
        0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Big Endian)   to float[]
    // float[] = {0x3F8CCCCD,0x3F99999A,0x3FA66666,0x40066666,0x400CCCCD,0x40133333,
        0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,0x00000000,
        0x00000000,0x00000000,0x00000000} (Big Endian)
    // float[] = { 1.1,1.2,1.3,2.1,2.2,2.3,0,0,0,0,0,0,0,0}
```

19.2 eip_read_input_int()

Read the input table content and convert the data to the 32-bit integer.

Syntax 1

int[] **eip_read_input_int**(
    int,
    int,
    int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **eip_read_input_int**(
    int,
    int
)

Parameters

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to an int array based on Little Endian (DCBA) or Big Endian.

```
int[] var_ia = eip_read_input_int(112,12,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
var_ia = eip_read_input_int(112,11,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF} (Little Endian)      to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
    // int[] = {32767,99999,16744448}
var_ia = eip_read_input_int(112,10,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80} (Little Endian)to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00008000} (Little Endian)
    // int[] = {32767,99999,32768}

var_ia = eip_read_input_int(112,12,1)
```

```
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Big Endian)  to int[]
        // int[] = {0xFF7F0000,0x9F860100,0x0080FFFF} (Big Endian)
        // int[] = {-8454144,-1618607872,8454143}

    var_ia = eip_read_input_int(112,12,2)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}

    var_ia = eip_read_input_int(112,12)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}
```

Syntax 3

```
int eip_read_input_int(
    int
)
```

Parameter

int	Starting address *Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = eip_read_input_int(112)
    // byte[] = {0xE4,0x07,0x00,0x00} (Little Endian)  to int
    // int = 0x000007E4 (Little Endian)
    // int = 2020
var_i = eip_read_input_int(112)
    // byte[] = {0x00,0x00,0x07,0xE4} (Big Endian)          to int
    // int = 0x000007E4 (Big Endian)
    // int = 2020
```

19.3 eip_read_input_float()

Read the input table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **eip_read_input_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **eip_read_input_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = eip_read_input_float(172,12,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}
var_fa = eip_read_input_float(172,11,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00400000} (Little Endian)
    // float[] = {1.0,2.0,5.877472E-39}
var_fa = eip_read_input_float(172,10,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00000000} (Little Endian)
    // float[] = {1.0,2.0,0.0}
```

```
var_fa = eip_read_input_float(172,12,1)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x0000803F,0x00000040,0x00004040} (Big Endian)
    // float[] = {4.600603E-41,8.96831E-44,2.304856E-41}

var_fa = eip_read_input_float(172,12,2)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}

var_fa = eip_read_input_float(172,12)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}
```

Syntax 3

```
float eip_read_input_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big Endian (ABCD).

Return

Float	Return data in a floating-point number.

Note

```
float var_f = eip_read_input_float(172)
    // byte[] = {0x00,0x00,0x80,0x3F} (Little Endian) to float
    // float = 0x3F800000 (Little Endian)
    // float = 1.0
var_f = eip_read_input_float(172)
    // byte[] = {0x3F,0x80,0x00,0x00} (Big Endian) to float
    // float = 0x3F800000 (Big Endian)
    // float = 1.0
```

19.4 eip_read_input_string()

Read the input table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string eip_read_input_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = eip_read_input_string(104,16)
    // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "TM5-700"

var_s = eip_read_input_string(104,32)
    // byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "01060112"

var_s = eip_read_input_string(104,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                 0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明機器人 1234"
var_s = eip_read_input_string(104,10)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E}
    // string = "abcd 達明"
var_s = eip_read_input_string(104,8)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6}
    // string = "abcd 達"
```

19.5 eip_read_input_bit()

Read the input table content and retrieve the nth bit value of the data byte.

Syntax 1

```
byte eip_read_input_bit(
    int,
    int
)
```

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = eip_read_input_bit(104,0)
    // 0x30     get bit: "0"
    // 0
var_b = eip_read_input_bit(104,5)
    // 0x30     get bit: "5"
    // 1
```

Syntax 2

```
byte eip_read_input_bit(
    string,
    int
)
```

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = eip_read_input_bit("O2T_Register_Bit",0)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // 1    get bit: "0"
var_b = eip_read_input_bit("O2T_Register_Bit",17)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // 0    get bit: "17"
```

Syntax 3

```
byte[] eip_read_input_bit(
```

int,
int,
int
)

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = eip_read_input_bit(104,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = eip_read_input_bit(104,12,8)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // byte[] = {1,1,0,1,0,0,1,1}
```

Syntax 4

```
byte[] eip_read_input_bit(
    string,
    int,
    int
)
```

Parameter

string	Item name
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = eip_read_input_bit("O2T_Register_Bit",0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = eip_read_input_bit("O2T_Register_Bit",12,8)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1,…}    // total
    // byte[] = {1,1,0,1,0,0,1,1}
```

19.6 eip_read_output()

Read the output table content.

Syntax 1

byte[] **eip_read_output**(
int,
int
)

Parameter

int	Starting address
int	The address length to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = eip_read_output(300,8)
    // {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32}
```

Syntax 2

byte **eip_read_output**(
int
)

Parameter

int	Starting address

Return

Byte	Return data in byte.

Note

```
byte var_b = eip_read_output(300)
    // 0x30
```

Syntax 3

? **eip_read_output**(
string,
int,
int
)

Parameter

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **eip_read_output**(
string,
int,

)

Parameter

string Item name

int The starting shifted address of the item

Return

? The data type returned by the item defined in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **eip_read_output**(

string

)

Parameter

string Item name

Return

? The data type returned by the item defined in the communication data table.

* Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = eip_read_output("ManualAuto",0,1)
    // 0x02
var_b = eip_read_output("ManualAuto",0)
    // 0x02
var_b = eip_read_output("ManualAuto")
    // 0x02

byte[] var_ba = eip_read_output("Error_Code",0,4)
    // {0x00,0x04,0x80,0x0C}
var_ba = eip_read_output("Error_Code",0,2)
    // {0x00,0x04}
var_ba = eip_read_output("Error_Code")
    // {0x00,0x04,0x80,0x0C}

int var_i = eip_read_output("Current_Time_Year")
    // byte[] = {0x00,0x00,0x07,0xE4} (Little Endian)  to int
    // int = 0x000007E4 (Little Endian)
    // int = 2020

int[] var_ia = eip_read_output("T2O_Register_Int",0,12)
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03} (Little Endian)
    to int[]
    // int[] = { 0x00000001,0x00000002,0x00000003} (Little Endian)
```

```
    // int[] = {1,2,3}
var_ia = eip_read_output("T2O_Register_Int",12)
    // byte[] = {0x00,0x00,0x00,0x04,0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,
        0x00,0x00,0x00,0x08,0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,
        0x00,0x00,0x00,0x0C,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        (Little Endian) to int[]
    // int[] = {0x00000004,0x00000005,0x00000006,0x00000007,0x00000008,0x00000009,
        0x0000000A,0x0000000B,0x0000000C,0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {4,5,6,7,8,9,10,11,12,0,0,0}
var_ia = eip_read_output("T2O_Register_Int")
    // byte[] = {0x00,0x00,0x00,0x01,0x00,0x00,0x00,0x02,0x00,0x00,0x00,0x03,0x00,0x00,0x00,0x04,
        0x00,0x00,0x00,0x05,0x00,0x00,0x00,0x06,0x00,0x00,0x00,0x07,0x00,0x00,0x00,0x08,
        0x00,0x00,0x00,0x09,0x00,0x00,0x00,0x0A,0x00,0x00,0x00,0x0B,0x00,0x00,0x00,0x0C,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00000001,0x00000002,0x00000003,0x00000004,0x00000005,0x00000006,
        0x00000007,0x00000008,0x00000009,0x0000000A,0x0000000B,0x0000000C,
        0x00000000,0x00000000,0x00000000} (Little Endian)
    // int[] = {1,2,3,4,5,6,7,8,9,10,11,12,0,0,0}

float var_f = eip_read_output("Current_TCP_Mass")
    // byte[] = {0x40,0x40,0x00,0x00} (Big Endian)          to float
    // float = 0x40400000 (Big Endian)
    // float = 3.0

float[] var_fa = eip_read_output("Current_TCP_Value",4,12)
    // byte[] = {0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66} (Big Endian)  to float[]
    // float[] = {0x3F99999A,0x3FA66666,0x40066666} (Big Endian)
    // float[] = {1.2,1.3,2.1}

var_fa = eip_read_output("Current_TCP_Value",12)
    // byte[] = { 0x40,0x06,0x66,0x66,0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33} (Big Endian)
    to float[]
    // float[] = {0x40066666,0x400CCCCD,0x40133333} (Big Endian)
    // float[] = {2.1,2.2,2.3}
var_fa = eip_read_output("Current_TCP_Value")
    // byte[] = {0x3F,0x8C,0xCC,0xCD,0x3F,0x99,0x99,0x9A,0x3F,0xA6,0x66,0x66,0x40,0x06,0x66,0x66,
        0x40,0x0C,0xCC,0xCD,0x40,0x13,0x33,0x33} (Big Endian) to float[]
    // float[] = {0x3F8CCCCD,0x3F99999A,0x3FA66666,0x40066666,0x400CCCCD,0x40133333}
    (Big Endian)
    // float[] = { 1.1,1.2,1.3,2.1,2.2,2.3}

string var_s = eip_read_output ("ControlBoxID",0,16)
    // byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "01060112"
var_s = eip_read_output ("ControlBoxID",4,3)
    // byte[] = {0x30,0x31,0x31}
    // string = "011"
var_s = eip_read_output ("ControlBoxID")
```

```
// byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
// string = "01060112"
```

19.7 eip_read_output_int()

Read the output table content and convert the data to the 32-bit integer.

Syntax 1

int[] **eip_read_output_int**(
    int,
    int,
    int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **eip_read_output_int**(
    int,
    int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
* Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = eip_read_output_int(308,12,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
var_ia = eip_read_output_int(308,11,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF} (Little Endian)      to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
    // int[] = {32767,99999,16744448}
var_ia = eip_read_output_int(308,10,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80} (Little Endian)to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00008000} (Little Endian)
    // int[] = {32767,99999,32768}

var_ia = eip_read_output_int(308,12,1)
```

```
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0xFF7F0000,0x9F860100,0x0080FFFF} (Big Endian)
        // int[] = {-8454144,-1618607872,8454143}

    var_ia = eip_read_output_int(308,12,2)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}

    var_ia = eip_read_output_int(308,12)
        // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
        to int[]
        // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
        // int[] = {32767,99999,-32768}
```

Syntax 3

```
int eip_read_output_int(
    int
)
```

Parameter

int	Starting address * Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = eip_read_output_int(308)
    // byte[] = {0xE4,0x07,0x00,0x00} (Little Endian)  to int
    // int = 0x000007E4 (Little Endian)
    // int = 2020
var_i = eip_read_output_int(308)
    // byte[] = {0x00,0x00,0x07,0xE4} (Big Endian)          to int
    // int = 0x000007E4 (Big Endian)
    // int = 2020
```

19.8 eip_read_output_float()

Read the output table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **eip_read_output_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **eip_read_output_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = eip_read_output_float(368,12,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
    to float[]
    // float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
    // float[] = {1.0,2.0,3.0}
var_fa = eip_read_output_float(368,11,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00400000} (Little Endian)
    // float[] = {1.0,2.0,5.877472E-39}
var_fa = eip_read_output_float(368,10,0)
    // byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3F800000,0x40000000,0x00000000} (Little Endian)
    // float[] = {1.0,2.0,0.0}

var_fa = eip_read_output_float(368,12,1)
```

```
// byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
to float[]
// float[] = {0x0000803F,0x00000040,0x00004040} (Big Endian)
// float[] = {4.600603E-41,8.96831E-44,2.304856E-41}

var_fa = eip_read_output_float(368,12,2)
// byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
to float[]
// float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
// float[] = {1.0,2.0,3.0}

var_fa = eip_read_output_float(368,12)
// byte[] = {0x00,0x00,0x80,0x3F,0x00,0x00,0x00,0x40,0x00,0x00,0x40,0x40} (Little Endian)
to float[]
// float[] = {0x3F800000,0x40000000,0x40400000} (Little Endian)
// float[] = {1.0,2.0,3.0}
```

Syntax 3

```
float eip_read_output_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big

Return

float Return data in a floating-point number

Note

```
float var_f = eip_read_output_float(368)
// byte[] = {0x00,0x00,0x80,0x3F} (Little Endian) to float
// float = 0x3F800000 (Little Endian)
// float = 1.0
var_f = eip_read_output_float(368)
// byte[] = {0x3F,0x80,0x00,0x00} (Big Endian) to float
// float = 0x3F800000 (Big Endian)
// float = 1.0
```

19.9 eip_read_output_string()

Read the output table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string eip_read_output_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = eip_read_output_string(300,16)
    // byte[] = {0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "TM5-700"

var_s = eip_read_output_string(300,32)
    // byte[] = {0x30,0x31,0x30,0x36,0x30,0x31,0x31,0x32,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                 0x54,0x4D,0x35,0x2D,0x37,0x30,0x30,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "01060112"

var_s = eip_read_output_string(300,32)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                 0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "abcd 達明機器人 1234"
var_s = eip_read_output_string(300,10)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E}
    // string = "abcd 達明"
var_s = eip_read_output_string(300,8)
    // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6}
    // string = "abcd 達"
```

19.10 eip_read_output_bit()

Read the output table content and retrieve the nth bit value of the data byte.

Syntax 1

```
byte eip_read_output_bit(
    int,
    int
)
```

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = eip_read_output_bit(300,0)
    // 0x30     get bit: "0"
    // 0
var_b = eip_read_output_bit(300,5)
    // 0x30     get bit: "5"
    // 1
```

Syntax 2

```
byte eip_read_output_bit(
    string,
    int
)
```

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte[] var_data = {57,184,12}
eip_write_output(300,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte var_b = eip_read_output_bit("T2O_Register_Bit",0)
    // 1
var_b = eip_read_output_bit("T2O_Register_Bit",17)
    // 0
```

Syntax 3

byte[] **eip_read_output_bit**(
int,
int,
int
)

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_data = {57,184,12}
eip_write_output(300,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte[] var_ba = eip_read_output_bit(300,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = eip_read_output_bit(300,12,8)
    // byte[] = {1,1,0,1,0,0,1,1}
```

Syntax 4

byte[] **eip_read_output_bit**(
string,
int,
int
)

Parameter

string	Item name
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_data = {57,184,12}
eip_write_output(300,var_data,3)
    // {00111001,10111000,00001100} (binary)
byte[] var_ba = eip_read_output_bit("T2O_Register_Bit",0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
var_ba = eip_read_output_bit("T2O_Register_Bit",12,8)
    // byte[] = {1,1,0,1,0,0,1,1}
```

19.11 eip_write_output()

Write data to the output table.

Syntax 1

bool **eip_write_output**(
int,
?,
int
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	The maximum amount of the address to write	
	> 0	Valid data length. Write by the amount of the address.
	<= 0	Invalid data length. Write by the complete length of the data to write.

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 2

bool **eip_write_output**(
int,
?
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 1. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 3

bool **eip_write_output**(
int,

```
    ?,
    int,
    int
)
```

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	Starting address of the data to write	
int	The amount of the address to write	

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

** Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
byte var_data = 255
eip_write_output(300,var_data,1)
byte var_b = eip_read_output(300)
    // 0xFF

byte[] var_data = {1,127,255}
eip_write_output(300,var_data,3)
byte[] var_ba = eip_read_output(300,3)
    // {0x01,0x7F,0xFF}
eip_write_output(300,var_data,2)
var_ba = eip_read_output(300,3)
    // {0x01,0x7F,0x00}
eip_write_output(300,var_data,-1)
var_ba = eip_read_output(300,3)
    // {0x00,0x7F,0xFF}

int var_data = 32767
eip_write_output(308,var_data,4)
int var_i = eip_read_output_int(308)
    // byte[] = {0xFF,0x7F,0x00,0x00} (Little Endian)  to int
    // int = 0x00007FFF (Little Endian)
    // int = 32767
eip_write_output(308,var_data,1)
var_i = eip_read_output_int(308)
    // byte[] = {0xFF,0x00,0x00,0x00} (Little Endian)  to int
    // int = 0x000000FF (Little Endian)
    // int = 255

int[] var_data = {32767,99999,-32768}
```

```
eip_write_output(308,var_data,12)
int[] var_ia = eip_read_output_int(308,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
eip_write_output(308,var_data,3)
var_ia = eip_read_output_int(308,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x00000000,0x00000000} (Little Endian)
    // int[] = {32767,0,0}
eip_write_output(308,var_data,11)
var_ia = eip_read_output_int(308,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0x00} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0x00FF8000} (Little Endian)
    // int[] = {32767,99999,16744448}
eip_write_output(308,var_data,4,4)
var_ia = eip_read_output_int(308,12)
    // byte[] = {0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to int[]
    // int[] = {0x0001869F,0x00000000,0x00000000} (Little Endian)
    // int[] = {99999,0,0}

float var_data = -10.0
eip_write_output(368,var_data,4)
float var_f = eip_read_output_float(368)
    // byte[] = {0x00,0x00,0x20,0xC1} (Little Endian)  to float
    // float = 0xC1200000 (Little Endian)
    // float = -10.0
eip_write_output(368,var_data,1)
var_f = eip_read_output_float(368)
    // byte[] = {0x00,0x00,0x00,0x00} (Little Endian)  to float
    // float = 0x00000000 (Little Endian)
    // float = 0

float[] var_data = {-10.0,3.3,123.45}
eip_write_output(368,var_data,12)
float[] var_fa = eip_read_output_float(368,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
    to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10,3.3,123.45}
eip_write_output(368,var_data,3)
var_fa = eip_read_output_float(368,12)
    // byte[] = {0x00,0x00,0x20,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to float[]
```

```
        // float[] = {0x00200000,0x00000000,0x00000000} (Little Endian)
        // float[] = {2.938736E-39,0,0}
    eip_write_output(368,var_data,11)
    var_fa = eip_read_output_float(368,12)
        // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x00} (Little Endian)
        to float[]
        // float[] = {0xC1200000,0x40533333,0x00F6E666} (Little Endian)
        // float[] = {-10,3.3,2.267418E-38}
    eip_write_output(368,var_data,4,4)
    var_fa = eip_read_output_float(368,12)
        // byte[] = {0x33,0x33,0x53,0x40,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian)
        to float[]
        // float[] = {0x40533333,0x00000000,0x00000000} (Little Endian)
        // float[] = {3.3,0,0}

    string var_data = "abcd 達明機器人 1234"
    eip_write_output(300,var_data,32)
    string var_s = eip_read_output_string(300,32)
        // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,
                0xE4,0xBA,0xBA,0x31,0x32,0x33,0x34,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        // string = "abcd 達明機器人 1234"
    eip_write_output(300,var_data,10)
    var_s = eip_read_output_string(300,32)
        // byte[] = { 0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x98,0x8E,0x00,0x00,0x00,0x00,0x00,0x00,
                0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        // string = "abcd 達明"
    eip_write_output(300,var_data,8)
    var_s = eip_read_output_string(300,32)
        // byte[] = {0x61,0x62,0x63,0x64,0xE9,0x81,0x94,0xE6,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
                0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
        // string = "abcd 達"
    eip_write_output(300,var_data,4,15)
    var_s = eip_read_output_string(300,15)
        // byte[] = {0xE9,0x81,0x94,0xE6,0x98,0x8E,0xE6,0xA9,0x9F,0xE5,0x99,0xA8,0xE4,0xBA,0xBA}
        // string = "達明機器人"
```

Syntax 4

```
bool eip_write_output(
    string,
    int,
    ?
    int,
    int
)
```

Parameter

string	Item name
int	The starting shifted address of the item
?	The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

int Starting address of the data to write

int The amount of the address to write

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

** Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 5

bool **eip_write_output**(
    string,
    int,
    ?
    int
)

Parameter

string Item name

int The starting shifted address of the item

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

int Starting address of the data to write

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 6

bool **eip_write_output**(
    string,
    int,
    ?
)

Parameter

string Item name

int The starting shifted address of the item

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool True Write successfully.

	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting address to write and write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 7

bool **eip_write_output**(
string,
?
)

Parameter

string		Item name
?		The data to write * Available data types include **byte,byte[],int,int[],float,float[],string**

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting shifted address and the starting address to write as well as write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
int[] var_data = {32767,99999,-32768}
eip_write_output("T2O_Register_Int",0,var_data,0,12)
int[] var_ia = eip_read_output_int(308,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)
    to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
eip_write_output("T2O_Register_Int",4,var_data,4,4)
var_ia = eip_read_output_int(308,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00} (Little Endian)
    to int[]
    // int[] = {0x00000000,0x0001869F,0x00000000} (Little Endian)
    // int[] = {0,99999,0}
eip_write_output("T2O_Register_Int",4,var_data)
var_ia = eip_read_output_int(308,20)
    // byte[] = {0x00,0x00,0x00,0x00,0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF,
        0x00,0x00,0x00,0x00} (Little Endian)  to int[]
    // int[] = {0x00000000,0x00007FFF,0x0001869F,0xFFFF8000,0x00000000} (Little Endian)
    // int[] = {0,32767,99999,-32768,0}
```

```
float[] var_data = {-10.0,3.3,123.45}
eip_write_output("T2O_Register_Float",0,var_data,0,12)
float[] var_fa = eip_read_output_float(368,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
    to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10,3.3,123.45}
eip_write_output("T2O_Register_Float",4,var_data,4,8)
var_fa = eip_read_output_float(368,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian)
    to float[]
    // float[] = {0x00000000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,3.3,123.45}
eip_write_output("T2O_Register_Float",8,var_data)
var_fa = eip_read_output_float(368,20)
    // byte[] = {0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,
        0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0x00000000,0x00000000,0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,0,-10,3.3,123.45}
```

19.12 eip_write_output_bit()

Write content to the nth bit value of the data byte in the output table.

Syntax 1

bool **eip_write_output_bit**(
    int,
    int,
    int
)

Parameter

int	Starting address	
int	The nth bit value	
int	The data to write *Data in bit will write in int.	

Return

Bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
eip_write_output(300,var_data)
byte var_b = eip_read_output(300)
    // 0xF0
eip_write_output_bit(300,1,1)
var_b = eip_read_output_bit(300,1)
    // 0xF2     get bit: "1"
    // 1
eip_write_output_bit(300,7,0)
var_b = eip_read_output_bit(300,7)
    // 0x72     get bit: "7"
    // 0
```

Syntax 2

bool **eip_write_output_bit**(
    string,
    int,
    int
)

Parameter

string	Item name
int	The nth bit value
int	The data to write *Data in bit will write in int.

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
```

```
eip_write_output(300,var_data)
byte var_b = eip_read_output(300)
    // 0xF0
eip_write_output_bit("T2O_Register_Bit",1,1)
var_b = eip_read_output_bit(300,1)
    // 0xF2     get bit: "1"
    // 1
eip_write_output_bit("T2O_Register_Bit",7,0)
var_b = eip_read_output_bit(300,7)
    // 0x72     get bit: "7"
    // 0
```

Syntax 3

```
bool eip_write_output_bit(
    int,
    int,
    byte[],
    int,
    int
)
```

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit of the data to write	
int	The bit amount of the data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 4

```
bool eip_write_output_bit(
    int,
    int,
    byte[],
    int
)
```

Parameter

int	Starting address
int	The nth bit value
byte[]	The data to write
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int	The starting bit of the data to write

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

*Same as syntax 3. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 5

```
bool eip_write_output_bit(
    int,
    int,
    byte[]
)
```

Parameter

int	Starting address
int	The nth bit value
byte[]	The data to write
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

*Same as syntax 3. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
eip_write_output_bit(300,0,var_data,0,20)
byte[] var_ba = eip_read_output (300,0,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = eip_read_output_bit(300,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
eip_write_output_bit(300,3,var_data,5,10)
var_ba = eip_read_output (300,0,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = eip_read_output_bit(300,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

Syntax 6

```
bool eip_write_output_bit(
    string,
    int,
    byte[],
    int,
    int
)
```

Parameter

string Item name
int Starting bit
byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int The starting bit to write data
int The bit amount of the data to write

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 7

bool **eip_write_output_bit**(
string,
int,
byte[],
int
)

Parameter

string Item name
int Starting bit
byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int The starting bit to write data

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

*Same as syntax 6. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 8

bool **eip_write_output_bit**(
string,
int,
byte[]
)

Parameter

string Item name
int Starting bit
byte[] The data to write
*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Return

bool True Write successfully.
False Write unsuccessfully. 1. Unable to send correctly and receive .

Note

*Same as syntax 6. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
eip_write_output_bit("T2O_Register_Bit",0,var_data,0,20)
byte[] var_ba = eip_read_output (300,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = eip_read_output_bit(300,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
eip_write_output_bit("T2O_Register_Bit",3,var_data,5,10)
var_ba = eip_read_output (300,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = eip_read_output_bit(300,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

20. EtherCAT Functions

The robot communicates with external controllers via the EtherCAT communication protocol. In the mechanism of the EtherCAT communication protocol, the robot works as an EtherCAT IO device for external devices to read and write the robot data. At the same time, TMflow can monitor the robot's "data table received from external devices" and "data table sent to external devices" via EtherCAT functions. Additionally, TMflow can modify the user-defined areas within the "data table sent to external devices."

Communication Data Table

The data table is composed of input data and output data. The Input Data Table is for external devices posting on the robot, and the Output Data Table is for the robot sending to external devices. Both data tables come with the System Definition Section and the Custom Definition Section for data.

1. System Definition Section: Items and settings are defined by the robot, and the data contents are updated by the robot or external devices. The defined items are robot status relevant such as robot bases, project status, control box status, or input/output status relevant such as digital I/Os and analog I/Os. Users can use EtherCAT functions to read the input data table and the output data table in the system definition section.
2. Custom Definition Section: Items and settings are defined by users, and the data contents are updated by users or external devices. While the project editing, users can use EtherCAT functions to read and write the output data table in the custom definition section or read input data table in the custom definition section. They can also use the custom definition section as a data exchange register between the project and external devices.

Communication Data Table (at the robot's viewpoint)	Data Section	TMflow EtherCAT Function Permissions	External Device Permissions
Input Data Table	System Definition Section	Read	Write
	Custom Definition Section	Read	Write
Output Data Table	System Definition Section	Read	Read
	Custom Definition Section	Read/Write	Read

20.1 ethercat_read_input()

Read the input table content.

Syntax 1

byte[] **ethercat_read_input**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = ethercat_read_input(4,20)
    //
    {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54,0x65,0x73,0x74,0x5F,0x31,0x00,0x00,0x00,
    0x00,0x00}
```

Syntax 2

byte **ethercat_read_input**(
int
)

Parameter

int	Starting address

Return

byte	Return data in byte.

Note

```
byte var_b = ethercat_read_input(4)
    // 0x45
```

Syntax 3

? **ethercat_read_input**(
string,
int,
int
)

Parameter

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **ethercat_read_input**(
string,
int
)

Parameter

string	Item name
int	The starting shifted address of the item

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **ethercat_read_input**(
    string
)

Parameter

string	Item name

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = ethercat_read_input("CameraLightMask")
    // 0x01

byte[] var_ba = ethercat_read_input("CtrlBox_DO",0,2)
    // {0x99,0x66}
var_ba = ethercat_read_input("CtrlBox_DO",1,1)
    // {0x66}
var_ba = ethercat_read_input("CtrlBox_DO")
    // {0x99,0x66}

float var_f = ethercat_read_input("CtrlBox_AO")
    // byte[] = {0xA4,0x70,0x9D,0x3F} (Little Endian) to float
    // float = 0x3F9D70A4 (Little Endian)
    // float = 1.23

string var_s = ethercat_read_input("AutoRun_ProjectName",0,10)
    // byte[] = {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54}
    // string = EtherCAT_T

var_s = ethercat_read_input("AutoRun_ProjectName",3,3)
    // byte[] = {0x65,0x72,0x43}
    // string = erC
var_s = ethercat_read_input("AutoRun_ProjectName")
    // byte[] =
    0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54,0x65,0x73,0x74,0x5F,0x31,0x00,0x00,0x00,0
    x00,0x00}
    // string = EtherCAT_Test_1
```

20.2 ethercat_read_input_int()

Read the input table content and convert the data to the 32-bit integer.

Syntax 1

int[] **ethercat_read_input_int**(
int,
int,
int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **ethercat_read_input_int**(
int,
int
)

Parameters

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to an int array based on Little Endian (DCBA) or Big Endian.

```
int[] var_ia = ethercat_read_input_int(72,4,0)
    // byte[] = {0xB1,0x68,0xDE,0x3A} (Little Endian)to int[]
    // int[] = {0x3ADE68B1} (Little Endian)
    // int[] = {987654321}
var_ia = ethercat_read_input_int(72,1,0)
    // byte[] = {0xB1} (Little Endian)  to int[]
    // int[] = {0x000000B1} (Little Endian)
    // int[] = {177}
var_ia = ethercat_read_input_int(72,4)
    // byte[] = {0xB1,0x68,0xDE,0x3A} (Little Endian)to int[]
    // int[] = {0x3ADE68B1} (Little Endian)
    // int[] = {987654321}
```

Syntax 3

```
int ethercat_read_input_int(
    int
)
```

Parameter

int	Starting address *Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = ethercat_read_input_int(72)
    // byte[] = {0xB1,0x68,0xDE,0x3A} (Little Endian)to int
    // int = 0x3ADE68B1 (Little Endian)
    // int = 987654321
```

20.3 ethercat_read_input_float()

Read the input table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **ethercat_read_input_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **ethercat_read_input_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = ethercat_read_input_float(56,8,0)
    // byte[] = {0xA4,0x70,0x9D,0x3F,0x85,0xEB,0x91,0xC0} (Little Endian)      to float[]
    // float[] = {0x3F9D70A4,0xC091EB85} (Little Endian)
    // float[] = {1.23,-4.56}
var_fa = ethercat_read_input_float(56,4,0)
    // byte[] = {0xA4,0x70,0x9D,0x3F} (Little Endian) to float[]
    // float[] = {0x3F9D70A4} (Little Endian)
    // float[] = {1.23}
var_fa = ethercat_read_input_float(56,2,0)
    // byte[] = {0xA4,0x70} (Little Endian)  to float[]
    // float[] = {0x000070A4} (Little Endian)
    // float[] = {0}
var_fa = ethercat_read_input_float(56,8)
    // byte[] = {0xA4,0x70,0x9D,0x3F,0x85,0xEB,0x91,0xC0} (Little Endian)      to float[]
    // float[] = {0x3F9D70A4,0xC091EB85} (Little Endian)
```

```
// float[] = {1.23,-4.56}
```

Syntax 3

```
float ethercat_read_input_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big Endian (ABCD).

Return

Float	Return data in a floating-point number.

Note

```
int var_f = ethercat_read_input_float(132)
    // byte[] = {0xE1,0x7A,0xFC,0x40} (Little Endian) to float
    // float = 0x40FC7AE1 (Little Endian)
    // float = 7.89
```

20.4 ethercat_read_input_string()

Read the input table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string eip_read_input_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = ethercat_read_input_string(4,20)
    // byte[] =
    {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54,0x65,0x73,0x74,0x5F,0x31,0x00,0x00,0x00,
    0x00,0x00}
    // string = EtherCAT_Test_1
var_s = ethercat_read_input_string (4,10)
    // byte[] = {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54}
    // string = EtherCAT_T
```

20.5 ethercat_read_input_bit()

Read the input table content and retrieve the nth bit value of the data byte.

Syntax 1

byte **ethercat_read_input_bit**(
int,
int
)

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = ethercat_read_input_bit(50,0)
    // byte[] = {0x99}
    // 1
var_b = ethercat_read_input_bit(50,7)
    // byte[] = {0x99}
    // 1
```

Syntax 2

byte **ethercat_read_input_bit**(
string,
int
)

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = ethercat_read_input_bit("Register_Bit",0)
    // byte[] = {0x99}
    // 1
var_b = ethercat_read_input_bit("Register_Bit",7)
    // byte[] = {0x99}
    // 1
```

Syntax 3

byte[] **ethercat_read_input_bit**(

int,
int,
int
)

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = ethercat_read_input_bit(50,0,16)
    // byte[] = {0x99,0x66}
    // byte[] = {1,0,0,1,1,0,0,1,0,1,1,0,0,1,1,0}
var_ba = ethercat_read_input_bit (50,8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = ethercat_read_input_bit (50,6,4)
    // byte[] = {0x99,0x66}
    // byte[] = {0,1,0,1}
```

Syntax 4

byte[] **ethercat_read_input_bit**(
string,
int,
int
)

Parameter

string	Item name
int	Starting bit
int	he amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = ethercat_read_input_bit("Register_Bit",0,16)
    // byte[] = {0xEE,0x66}
    // byte[] = {0,1,1,1,0,1,1,1,0,1,1,0,0,1,1,0}
var_ba = ethercat_read_input_bit ("Register_Bit",8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = ethercat_read_input_bit ("Register_Bit",6,4)
    // byte[] = {0xEE,0x66}
    // byte[] = {1,1,0,1}
```

20.6 ethercat_read_output()

Read the output table content.

Syntax 1

byte[] **ethercat_read_output**(
    int,
    int
)

Parameter

int	Starting address
int	The address length to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = ethercat_read_output(40,12)
    // {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54,0x65,0x73}
```

Syntax 2

byte **ethercat_read_output**(
    int
)

Parameter

int	Starting address

Return

byte	Return data in byte.

Note

Same as syntax 1. Fill 1 as the last parameter int by default.

```
byte var_b = ethercat_read_output(40)
    // 0x45
```

Syntax 3

? **ethercat_read_output**(
string,
int,
int
)

Parameter

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **ethercat_read_output**(
string,
int
)

Parameter

string	Item name
int	The starting shifted address of the item

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **ethercat_read_output**(
    string
)

Parameter

string	Item name

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = ethercat_read_output("ManualAuto",0,1)
    // 0x01
var_b = ethercat_read_output("ManualAuto",0)
    // 0x01
var_b = ethercat_read_output("ManualAuto")
    // 0x01

byte[] var_ba = ethercat_read_output("Error_Code",0,4)
    // {0x04,0x44,0x04,0x00}
var_ba = ethercat_read_output("Error_Code",0,2)
    // {0x04,0x44}
var_ba = ethercat_read_output("Error_Code")
    // {0x04,0x44,0x04,0x00}

int var_i = ethercat_read_output("Current_Time_Year")
    // byte[] = {0xE8,0x07,0x00,0x00} (Little Endian) to int
    // int = 0x000007E8 (Little Endian)
    // int = 2024
```

```
int[] var_ia = ethercat_read_output("Current_Time_Year")
    // byte[] = {0xE8,0x07,0x00,0x00} (Little Endian)  to int[]
    // int16[] = {0x000007E8} (Little Endian)
    // int[] = {2024}

float var_f = ethercat_read_output("CtrlBox_AO")
    // byte[] = {0x9D,0x67,0x9D,0x3F} (Little Endian) to float[]
    // float = 0x3F9D679D (Little Endian)
    // float = 1.23

float[] var_fa = ethercat_read_output("Coord_CurrBase_Tool",4,12)
    // byte[] = {0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42} (Little Endian)     to
    float[]
    // float[] = {0xC37C999A,0x445EECCD,0x42B40000} (Little Endian)
    // float[] = {-252.6,891.7,90}

var_fa = ethercat_read_output("Coord_CurrBase_Tool",4)
    // byte[] =
    {0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,0x00,0x00,0x00,0x00,0x00,0x0
    0,0x00,0x00} (Little Endian)       to float[]
    // float[] = {0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little Endian)
    // float[] = {-252.6,891.7,90,0,0}

var_fa = ethercat_read_output("Coord_CurrBase_Tool")
    // byte[] =
    {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Big Endian)    to float[]
    // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little
    Endian)
    // float[] = {0.01,-252.6,891.7,90,0,0}
```

20.7 ethercat_read_output_int()

Read the output table content and convert the data to the 32-bit integer.

Syntax 1

int[] **ethercat_read_output_int**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **ethercat_read_output_int**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as syntax 1. Fill 2 as the last parameter int by default.

* Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = ethercat_read_output_int(216,12,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)  to
    int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
var_ia = ethercat_read_output_int(216,6,0)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x0000869F} (Little Endian)
    // int[] = {32767,34463}
var_ia = ethercat_read_output_int(216,1,0)
    // byte[] = {0xFF} (Little Endian)  to int[]
    // int[] = {0x000000FF} (Little Endian)
    // int[] = {255}
var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian)  to
    int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
```

Syntax 3

```
int ethercat_read_output_int(
    int
)
```

Parameter

int	Starting address * Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = ethercat_read_output_int(216)
    // byte[] = {0xFF,0x7F,0x00,0x00} (Little Endian)  to int[]
    // int[] = 0x00007FFF (Little Endian)
    // int = 32767
```

20.8 ethercat_read_output_float()

Read the output table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **ethercat_read_output_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **ethercat_read_output_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as syntax 1. Fill 2 as the last parameter int by default.

*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = ethercat_read_output_float(120,24,0)
    // byte[] =
    {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little
    Endian)
    // float[] = {0.01,-252.6,891.7,90,0,0}
var_fa = ethercat_read_output_float(120,12,0)
    // byte[] = {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44} (Little Endian)  to
    float[]
    // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD} (Little Endian)
    // float[] = {0.01,-252.6,891.7}
var_fa = ethercat_read_output_float(120,2,0)
    // byte[] = {0x0A,0xD7} (Little Endian) to float[]
    // float[] = {0x0000D70A} (Little Endian)
```

```
        // float[] = {0}
    var_fa = ethercat_read_output_float(120,24)
        // byte[] =
        {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
        //  float[] = {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little
        Endian)
        // float[] = {0.01,-252.6,891.7,90,0,0}
```

Syntax 3

```
float ethercat_read_output_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big

Return

float	Return data in a floating-point number

Note

```
float var_f = ethercat_read_output_float(120)
    // byte[] = {0x0A,0xD7,0x23,0x3C} (Little Endian) to float[]
    // float[] = 0x3C23D70A (Little Endian)
    // float = 0.01
```

20.9 ethercat_read_output_string()

Read the output table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string ethercat_read_output_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = ethercat_read_output_string(40,20)
    // byte[] =
    {0x45,0x74,0x68,0x65,0x72,0x43,0x41,0x54,0x5F,0x54,0x65,0x73,0x74,0x5F,0x31,0x00,0x00,0x00,
    0x00,0x00}
    // string = "EtherCAT_Test_1"
var_s = ethercat_read_output_string(40,3)
    // byte[] = {0x45,0x74,0x68}
    // string = "Eth"
```

20.10 ethercat_read_output_bit()

Read the output table content and retrieve the nth bit value of the data byte.

Syntax 1

byte **ethercat_read_output_bit**(
int,
int
)

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

Byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = ethercat_read_output_bit(186,0)
    // byte[] = {0x99}
    // 1
var_b = ethercat_read_output_bit(186,7)
    // byte[] = {0x99}
    // 1
```

Syntax 2

byte **ethercat_read_output_bit**(
string,
int
)

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = ethercat_read_output_bit("Register_Bit",0)
    // byte[] = {0x84}
    // 0
var_b = ethercat_read_output_bit("Register_Bit",7)
    // byte[] = {0x84}
    // 1
```

Syntax 3

byte[] **ethercat_read_output_bit**(

int,
int,
int
)

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = ethercat_read_output_bit(186,0,16)
    // byte[] = {0x99,0x66}
    // byte[] = {1,0,0,1,1,0,0,1,0,1,1,0,0,1,1,0}
var_ba = ethercat_read_output_bit (186,8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = ethercat_read_output_bit (186,6,4)
    // byte[] = {0x99,0x66}
    // byte[] = {0,1,0,1}
```

Syntax 4

byte[] **ethercat_read_output_bit**(
string,
int,
int
)

Parameter

string	Item name
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = ethercat_read_output_bit("Register_Bit",0,16)
    // byte[] = {0x84,0xB7}
    // byte[] = {0,0,1,0,0,0,0,1,1,1,1,0,1,1,0,1}
var_ba = ethercat_read_output_bit ("Register_Bit",8,4)
    // byte[] = {0xB7}
    // byte[] = {1,1,1,0}
var_ba = ethercat_read_output_bit ("Register_Bit",6,4)
    // byte[] = {0x84,0xB7}
    // byte[] = {0,1,1,1}
```

20.11 ethercat_write_output()

Write data to the output table.

Syntax 1

bool **ethercat_write_output**(
int,
?,
int
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	The maximum amount of the address to write	
	> 0	Valid data length. Write by the amount of the address.
	<= 0	Invalid data length. Write by the complete length of the data to write.

Return

Bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 2

bool **ethercat_write_output**(
int,
?
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	

Return

Bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 1. Write with the full length of the data to write by default.
* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 3

bool **ethercat_write_output**(
int,

```
    ?,
    int,
    int
)
```

Parameter

int	Starting address
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**
int	Starting address of the data to write
int	The amount of the address to write

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

** Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
byte var_data = 255
ethercat_write_output(208,var_data,1)
byte var_b = ethercat_read_output(208)
    // 0xFF

byte[] var_data = {1,127,255}
ethercat_write_output(208,var_data,2)
byte[] var_ba = ethercat_read_output(208,3)
    // {0x01,0x7F,0x00}
ethercat_write_output(208,var_data,3)
var_ba = ethercat_read_output(208,3)
    // {0x01,0x7F,0xFF}
ethercat_write_output(208,var_data,-1)
var_ba = ethercat_read_output(208,3)
    // {0x01,0x7F,0xFF}

int var_data = 32767
ethercat_write_output(216,var_data,4)
var_i = ethercat_read_output_int(216)
    // byte[] = {0xFF,0x7F,0x00,0x00} (Little Endian) to int
    // int = 0x00007FFF (Little Endian)
    // int = 32767
ethercat_write_output(216,var_data,1)
var_i = ethercat_read_output_int(216)
    // byte[] = {0xFF,0x00,0x00,0x00} (Little Endian) to int
    // int = 0x000000FF (Little Endian)
    // int = 255
```

```
int[] var_data = {32767,99999,-32768}
ethercat_write_output(216,var_data,12)
int[] var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
ethercat_write_output(216,var_data,3)
var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x00000000,0x00000000} (Little Endian)
    // int[] = {32767,0,0}
ethercat_write_output(216,var_data,4,4)
var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x0001869F,0x00000000,0x00000000} (Little Endian)
    // int[] = {99999,0,0 }

float var_data = -10.0
ethercat_write_output(232,var_data,4)
float var_f = ethercat_read_output_float(232)
    // byte[] = {0x00,0x00,0x20,0xC1} (Little Endian) to float
    // float = 0xC1200000 (Little Endian)
    // float = -10.0
ethercat_write_output(232,var_data,1)
var_f = ethercat_read_output_int(232)
    // byte[] = {0x00,0x00,0x00,0x00} (Little Endian) to float
    // float = 0x00000000 (Little Endian)
    // float = 0

float[] var_data = {-10.0,3.3,123.45}
ethercat_write_output(232,var_data,12)
float[] var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10.0,3.3,123.45}
ethercat_write_output(232,var_data,3)
var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x00,0x00,0x20,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x00200000,0x00000000,0x00000000} (Little Endian)
    // float[] = {0,0,0}
ethercat_write_output(232,var_data,4,4)
var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x33,0x33,0x53,0x40,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x40533333,0x00000000,0x00000000} (Little Endian)
    // float[] = {3.3,0,0}

string var_data = "abcdefg1234567"
ethercat_write_output(208,var_data,16)
string var_s = ethercat_read_output_string(208,20)
```

```
        // byte[] =
        {0x61,0x62,0x63,0x64,0x65,0x66,0x67,0x31,0x32,0x33,0x34,0x35,0x36,0x37,0x00,0x00,0x00,0x00,0
        x00,0x00}
        // string = abcdefg1234567
    ethercat_write_output(208,var_data,8)
    var_s = ethercat_read_output_string(208,20)
        // byte[] =
        {0x61,0x62,0x63,0x64,0x65,0x66,0x67,0x31,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0
        x00,0x00}
        // string = abcdefg1
    ethercat_write_output(208,var_data,3,3)
    var_s = ethercat_read_output_string(208,20)
        // byte[] =
        {0x64,0x65,0x66,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0
        x00,0x00}
        // string = def
```

Syntax 4

```
bool ethercat_write_output(
    string,
    int,
    ?,
    int,
    int
)
```

Parameter

string	Item name
int	The starting shifted address of the item
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**
int	Starting address of the data to write
int	The amount of the address to write

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 5

```
bool ethercat_write_output(
    string,
    int,
    ?,
    int
)
```

Parameter

string	Item name
int	The starting shifted address of the item

? The data to write
* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

int Starting address of the data to write

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 6

```
bool ethercat_write_output(
    string,
    int,
    ?
)
```

Parameter

string Item name

int The starting shifted address of the item

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting address to write and write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 7

```
bool ethercat_write_output(
    string,
    ?
)
```

Parameter

string Item name

? The data to write

* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool True Write successfully.

False Write unsuccessfully.

1. If the data to write is an empty string or an empty

array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting shifted address and the starting address to write as well as write with the full length of the data to write by default.
* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
int[] var_data = {32767,99999,-32768}
ethercat_write_output("Register_Int",0,var_data,0,12)
int[] var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
ethercat_write_output("Register_Int",4,var_data,4,4)
var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00000000,0x0001869F,0x00000000} (Little Endian)
    // int[] = {0,99999,0}
ethercat_write_output("Register_Int",4,var_data)
var_ia = ethercat_read_output_int(216,12)
    // byte[] = {0x00,0x00,0x00,0x00,0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00} (Little Endian) to int[]
    // int[] = {0x00000000,0x00007FFF,0x0001869F} (Little Endian)
    // int[] = {0,32767,99999}

float[] var_data = {-10.0,3.3,123.45}
ethercat_write_output("Register_Float",0,var_data,0,12)
float[] var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10.0,3.3,123.45}
ethercat_write_output("Register_Float",4,var_data,4,8)
var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0x00000000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,3.3,123.45}
ethercat_write_output("Register_Float",4,var_data)
var_fa = ethercat_read_output_float(232,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40} (Little Endian) to float[]
    // float[] = {0x00000000,0xC1200000,0x40533333} (Little Endian)
    // float[] = {0,-10,3.3}
```

20.12 ethercat_write_output_bit()

Write content to the nth bit value of the data byte in the output table.

Syntax 1

```
bool ethercat_write_output_bit(
    int,
    int,
    int
)
```

Parameter

int	Starting address	
int	The nth bit value	
int	The data to write *Data in bit will write in int.	

Return

Bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
ethercat_write_output(208,var_data)
byte var_b = ethercat_read_output(208)
    // 0xF0
ethercat_write_output_bit(208,1,1)
var_b = ethercat_read_output_bit(208,1)
    // 0xF2     get bit: "1"
    // 1
ethercat_write_output_bit(208,7,0)
var_b = ethercat_read_output_bit(208,7)
    // 0x72     get bit: "7"
    // 0
```

Syntax 2

```
bool ethercat_write_output_bit(
    string,
    int,
    int
)
```

Parameter

string	Item name
int	The nth bit value
int	The data to write *Data in bit will write in int.

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

```
byte var_data = 240
ethercat_write_output(208,var_data)
byte var_b = ethercat_read_output(208)
    // 0xF0
ethercat_write_output_bit("Register_Bit",1,1)
var_b = ethercat_read_output_bit(208,1)
    // 0xF2      get bit: "1"
    // 1
ethercat_write_output_bit("Register_Bit",7,0)
var_b = ethercat_read_output_bit(208,7)
    // 0x72      get bit: "7"
    // 0
```

Syntax 3

bool **ethercat_write_output_bit**(
int,
int,
byte[],
int,
int
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit of the data to write	
int	The bit amount of the data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 4

bool **ethercat_write_output_bit**(
int,
int,
byte[],
int
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit of the data to write	

Return

Bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 3. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 5

bool **ethercat_write_output_bit**(
int,
int,
byte[]
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 3. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
ethercat_write_output_bit(208,0,var_data,0,20)
byte[] var_ba = ethercat_read_output(208,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = ethercat_read_output_bit (208,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
ethercat_write_output_bit(208,3,var_data,5,10)
var_ba = ethercat_read_output (208,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = ethercat_read_output_bit (208,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

Syntax 6

```
bool ethercat_write_output_bit(
    string,
    int,
    byte[],
    int,
    int
)
```

Parameter

string	Item name	
int	Starting bit	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit to write data	
int	The bit amount of the data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 7

bool **ethercat_write_output_bit**(
string,
int,
byte[],
int
)

Parameter

string	Item name	
int	Starting bit	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit to write data	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 6. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 8

bool **ethercat_write_output_bit**(
string,
int,
byte[]
)

Parameter

string	Item name	
int	Starting bit	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 6. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
ethercat_write_output_bit("Register_Bit",0,var_data,0,20)
byte[] var_ba = ethercat_read_output(208,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = ethercat_read_output_bit (208,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
```

```
ethercat_write_output_bit("Register_Bit ",3,var_data,5,10)
var_ba = ethercat_read_output (208,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = ethercat_read_output_bit (208,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

21. CC-Link Functions

The robot communicates with external controllers via the CC-Link communication protocol. In the mechanism of the CC-Link communication protocol, the robot works as an CC-Link IO device for external devices to read and write the robot data. Meanwhile, TMflow monitors the table of data receiving from external devices and the table of data sending to external devices with CC-Link functions as well as changes the custom definition section in the table of data sending to external devices.

Communication Data Table

The data table is composed of the input data and the output data. Input Data Table is for external devices posting on the robot, and Output Data Table is for the robot sending to external devices. Both of the data tables come with System Definition Section and Custom Definition Section for data.

1. System Definition Section: Items and settings are defined by the robot, and the data contents are updated by the robot or external devices. The defined items are robot status relevant such as robot bases, project status, control box status, or input/output status relevant such as digital I/Os and analog I/Os. Users can use CC-Link functions to read the input data table and the output data table in the system definition section.
2. Custom Definition Section: Items and settings are defined by users, and the data contents are updated by users or external devices. In the meantime of the project editing, users can use CC-Link functions to read and write the output data table in the custom definition section or read input data table in the custom definition section as well as use the custom definition section as a data exchange register between the project and external devices.

Communication Data Table (at the robot's viewpoint)	Data Section	TMflow CC Link Function Permissions	External Device Permissions
Input Data Table	System Definition Section	Read	Write
	Custom Definition Section	Read	Write
Output Data Table	System Definition Section	Read	Read
	Custom Definition Section	Read/Write	Read

21.1 cclink_read_input()

Read the input table content.

Syntax 1

byte[] **cclink_read_input**(
    int,
    int
)

Parameter

int	Starting address
int	The address amount to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = cclink_read_input(112,32)
    // {0x61,0x61,0x62,0x62,0x63,0x63,0x64,0x64,0x65,0x65,0x66,0x66,0x00,0x00,0x00,0x00,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
```

Syntax 2

byte **cclink_read_input**(
    int
)

Parameter

int	Starting address

Return

byte	Return data in byte.

Note

```
byte var_b = cclink_read_input(112)
    // 0x61
```

Syntax 3

? **cclink_read_input**(
string,
int,
int
)

Parameter

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **cclink_read_input**(
string,
int
)

Parameter

string	Item name
int	The starting shifted address of the item

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **cclink_read_input**(
    string
)

Parameter

string	Item name

Return

?	The data type returned by the item definition in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = cclink_read_input("CameraLightMask")
    // 0x00

byte[] var_ba = cclink_read_input("CtrlBox_DO",0,2)
    // {0xEE,0x66}
var_ba = cclink_read_input("CtrlBox_DO",1,1)
    // {0x66}
var_ba = cclink_read_input("CtrlBox_DO")
    // {0xEE,0x66}

float var_f = cclink_read_input("CtrlBox_AO")
    // byte[] = {0x71,0x3D,0x8A,0x40} (Little Endian) to float
    // float = 0x408A3D71 (Little Endian)
    // float = 4.32

string var_s = cclink_read_input("AutoRun_ProjectName",0,10)
    // byte[] = {0x61,0x61,0x62,0x62,0x63,0x63,0x64,0x64,0x65,0x65}
    // string = aabbccddee
var_s = cclink_read_input("AutoRun_ProjectName",3,3)
    // byte[] = {0x62,0x63,0x63}
    // string = bcc
var_s = cclink_read_input("AutoRun_ProjectName")
    // byte[] = {0x61,0x61,0x62,0x62,0x63,0x63,0x64,0x64,0x65,0x65,0x66,0x66,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = aabbccddeeff
```

21.2 cclink_read_input_int16()

Read the input table content and convert the data to the 16-bit integer.

Syntax 1

int[] **cclink_read_input_int16**(
    int,
    int,
    int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD). 3 Little-Endian 4 Big-Endian 5 Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **cclink_read_input_int16**(
    int,
    int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = cclink_read_input_int16(6,2,0)
    // byte[] = {0xEE,0x66} (Little Endian)  to int16[]
    // int16[] = {0x000066EE} (Little Endian)
    // int[] = {26350}
var_ia = cclink_read_input_int16(6,1,0)
    // byte[] = {0xEE} (Little Endian)  to int16[]
    // int16[] = {0x000000EE} (Little Endian)
    // int[] = {238}
var_ia = cclink_read_input_int16(6,2)
    // byte[] = {0xEE,0x66} (Little Endian)  to int16[]
    // int16[] = {0x000066EE} (Little Endian)
    // int[] = {26350}
```

Syntax 3

```
int cclink_read_input_int16(
    int
)
```

Parameter

int	Starting address *Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = cclink_read_input_int16(6)
    // byte[] = {0xEE,0x66} (Little Endian)  to int16
    // int16 = 0x000066EE (Little Endian)
    // int = 26350
```

21.3 cclink_read_input_int()

Read the input table content and convert the data to the 32-bit integer.

Syntax 1

int[] **cclink_read_input_int**(
    int,
    int,
    int
)

Parameters

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **cclink_read_input_int**(
    int,
    int
)

Parameters

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = cclink_read_input_int(6,4,0)
    // byte[] = {0xEE,0x66,0x0F,0x09} (Little Endian) to int[]
    // int[] = {0x090F66EE} (Little Endian)
    // int[] = {152004334}
var_ia = cclink_read_input_int(6,1,0)
    // byte[] = {0xEE} (Little Endian)  to int[]
    // int[] = {0x000000EE} (Little Endian)
    // int[] = {238}
var_ia = cclink_read_input_int(6,4)
    // byte[] = {0xEE,0x66,0x0F,0x09} (Little Endian) to int[]
    // int[] = {0x090F66EE} (Little Endian)
    // int[] = {152004334}
```

Syntax 3

```
int cclink_read_input_int(
    int
)
```

Parameter

int	Starting address *Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = cclink_read_input_int(6)
    // byte[] = {0xEE,0x66,0x0F,0x09} (Little Endian) to int
    // int = 0x090F66EE (Little Endian)
    // int = 152004334
```

21.4 cclink_read_input_float()

Read the input table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **cclink_read_input_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD). 3 Little-Endian 4 Big-Endian 5 Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **cclink_read_input_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as Syntax 1 with the parameter of the conversion of the read data defaults to 2.
*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = cclink_read_input_float(144,8,0)
    // byte[] = {0x71,0x3D,0x8A,0x40,0xA4,0x70,0x9D,0xBF} (Little Endian)      to float[]
    // float[] = {0x408A3D71,0xBF9D70A4} (Little Endian)
    // float[] = {4.32,-1.23}
var_fa = cclink_read_input_float(144,4,0)
    // byte[] = {0x71,0x3D,0x8A,0x40} (Little Endian) to float[]
    // float[] = {0x408A3D71} (Little Endian)
    // float[] = {4.32}
var_fa = cclink_read_input_float(144,2,0)
    // byte[] = {0x71,0x3D} (Little Endian)  to float[]
    // float[] = {0x00003D71} (Little Endian)
    // float[] = {0}
var_fa = cclink_read_input_float(144,8)
    // byte[] = {0x71,0x3D,0x8A,0x40,0xA4,0x70,0x9D,0xBF} (Little Endian)      to float[]
    // float[] = {0x408A3D71,0xBF9D70A4} (Little Endian)
```

```
// float[] = {4.32,-1.23}
```

Syntax 3

```
float cclink_read_input_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big Endian (ABCD).

Return

Float	Return data in a floating-point number.

Note

```
int var_f = cclink_read_input_float(144)
    // byte[] = {0x71,0x3D,0x8A,0x40} (Little Endian) to float
    // float = 0x408A3D71 (Little Endian)
    // float = 4.32
```

21.5 cclink_read_input_string()

Read the input table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string cclink_read_input_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = cclink_read_input_string(112,32)
    // byte[] = {0x61,0x61,0x62,0x62,0x63,0x63,0x64,0x64,0x65,0x65,0x66,0x66,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = aabbccddeeff
var_s = cclink_read_input_string (112,10)
    // byte[] = {0x61,0x61,0x62,0x62,0x63,0x63,0x64,0x64,0x65,0x65}
    // string = aabbccddee
```

21.6 cclink_read_input_bit()

Read the input table content and retrieve the nth bit value of the data byte.

Syntax 1

```
byte cclink_read_input_bit(
    int,
    int
)
```

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = cclink_read_input_bit(6,0)
    // byte[] = {0xEE}
    // 0
var_b = cclink_read_input_bit(6,7)
    // byte[] = {0xEE}
    // 1
var_b = cclink_read_input_bit(6,15)
    // byte[] = {0x66}
    // 0
```

Syntax 2

```
byte cclink_read_input_bit(
    string,
    int
)
```

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = cclink_read_input_bit("CtrlBox_DO",0)
    // byte[] = {0xEE}
    // 0
var_b = cclink_read_input_bit("CtrlBox_DO",7)
    // byte[] = {0xEE}
    // 1
```

```
var_b = cclink_read_input_bit("CtrlBox_DO",15)
    // byte[] = {0x66}
    // 0
```

Syntax 3

```
byte[] cclink_read_input_bit(
    int,
    int,
    int
)
```

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = cclink_read_input_bit(6,0,16)
    // byte[] = {0xEE,0x66}
    // byte[] = {0,1,1,1,0,1,1,1,0,1,1,0,0,1,1,0}
var_ba = cclink_read_input_bit (6,8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = cclink_read_input_bit (6,6,4)
    // byte[] = {0xEE,0x66}
    // byte[] = {1,1,0,1}
```

Syntax 4

```
byte[] cclink_read_input_bit(
    string,
    int,
    int
)
```

Parameter

string	Item name
int	Starting bit
int	he amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = cclink_read_input_bit("CtrlBox_DO",0,16)
    // byte[] = {0xEE,0x66}
```

```
        // byte[] = {0,1,1,1,0,1,1,1,0,1,1,0,0,1,1,0}
var_ba = cclink_read_input_bit ("CtrlBox_DO",8,4)
        // byte[] = {0x66}
        // byte[] = {0,1,1,0}
var_ba = cclink_read_input_bit ("CtrlBox_DO",6,4)
        // byte[] = {0xEE,0x66}
        // byte[] = {1,1,0,1}
```

21.7 cclink_read_output()

Read the output table content.

Syntax 1

byte[] **cclink_read_output**(
    int,
    int
)

Parameter

int	Starting address
int	The address length to read

Return

byte[]	Return data in a byte array.

Note

```
byte[] var_ba = cclink_read_output(160,12)
    // {0xE8,0x07,0x06,0x00,0x18,0x00,0x11,0x00,0x1A,0x00,0x23,0x00}
```

Syntax 2

byte **cclink_read_output**(
    int
)

Parameter

int	Starting address

Return

byte	Return data in byte.

Note

Same as syntax 1. Fill 1 as the last parameter int by default.

```
byte var_b = cclink_read_output(160)
    // 0xE8
```

Syntax 3

? **cclink_read_output**(
string,
int,
int
)

Parameter

string	Item name
int	The starting shifted address of the item
int	The amount of the addresses to read

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Syntax 4

? **cclink_read_output**(
string,
int
)

Parameter

string	Item name
int	The starting shifted address of the item

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

Syntax 5

? **cclink_read_output**(
    string
)

Parameter

string	Item name

Return

?	The data type returned by the item defined in the communication data table. * Data type includes **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Note

* Same as syntax 3. Fill 0 as the starting shifted address of the item and read to the end of the item by default.
* Reading data based on the configuration file Little Endian (DCBA) or Big Endian (ABCD).

```
byte var_b = cclink_read_output("ManualAuto",0,1)
    // 0x01
var_b = cclink_read_output("ManualAuto",0)
    // 0x01
var_b = cclink_read_output("ManualAuto")
    // 0x01

byte[] var_ba = cclink_read_output("Error_Code",0,4)
    // {0x0D,0x82,0x04,0x00}
var_ba = cclink_read_output("Error_Code",0,2)
    // {0x0D,0x82}
var_ba = cclink_read_output("Error_Code")
    // {0x0D,0x82,0x04,0x00}

int var_i = cclink_read_output("Current_Time_YY")
    // byte[] = {0xE8,0x07} (Little Endian) to int
    // int = 0x000007E8 (Little Endian)
    // int = 2024
```

```
int[] var_ia = cclink_read_output("Current_Time_YY")
    // byte[] = {0xE8,0x07} (Little Endian)  to int16[]
    // int16[] = {0x000007E8} (Little Endian)
    // int[] = {2024}

float var_f = cclink_read_output("CtrlBox_AO")
    // byte[] = {0x93,0x35,0xD3,0xC0} (Little Endian) to float[]
    // float = 0xC0D33593 (Little Endian)
    // float = -6.60

float[] var_fa = cclink_read_output("Coord_CurrBase_Tool",4,12)
    // byte[] = {0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42} (Little Endian)    to
    float[]
    // float[] = {0xC37C999A,0x445EECCD,0x42B40000} (Little Endian)
    // float[] = {-252.6,891.7,90}

var_fa = cclink_read_output("Coord_CurrBase_Tool",4)
    // byte[] = {0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
          0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little Endian)
    // float[] = {-252.6,891.7,90,0,0}

var_fa = cclink_read_output("Coord_CurrBase_Tool")
    // byte[] =
    {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Big Endian)    to float[]
    //  float[]  =  {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000}  (Little
    Endian)
    // float[] = {0.01,-252.6,891.7,90,0,0}
```

21.8 cclink_read_output_int16()

Read the output table content and convert the data to the 16-bit integer.

Syntax 1

int[] **cclink_read_output_int16**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **cclink_read_output_int16**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as syntax 1. Fill 2 as the last parameter int by default.

* Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = cclink_read_output_int16(160,12,0)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00,0x0B,0x00,0x20,0x00,0x0D,0x00} (Little Endian)  to int16[]
    // int16[] = {0x000007E8,0x00000006,0x00000019,0x0000000B,0x00000020,0x0000000D} (Little Endian)
    // int[] = {2024,6,25,11,32,13}
var_ia = cclink_read_output_int16(160,6,0)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00} (Little Endian) to int16[]
    // int16[] = {0x000007E8,0x00000006,0x00000019} (Little Endian)
    // int[] = {2024,6,25}
var_ia = cclink_read_output_int16(160,1,0)
    // byte[] = {0xE8} (Little Endian)  to int16[]
    // int16[] = {0x000000E8} (Little Endian)
    // int[] = {232}
var_ia = cclink_read_output_int16(160,12)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00,0x0B,0x00,0x2B,0x00,0x38,0x00} (Little Endian)  to int16[]
    // int16[] = {0x000007E8,0x00000006,0x00000019,0x0000000B,0x0000002B,0x00000038} (Little Endian)
    // int[] = {2024,6,25,11,43,56}
```

Syntax 3

```
int cclink_read_output_int16(
    int
)
```

Parameter

int	Starting address * Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = cclink_read_output_int16(160)
    // byte[] = {0xE8,0x07} (Little Endian)  to int16
    // int16 = 0x000007E8 (Little Endian)
    // int = 2024
```

21.9 cclink_read_output_int()

Read the output table content and convert the data to the 32-bit integer.

Syntax 1

int[] **cclink_read_output_int**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).
0	Little-Endian
1	Big-Endian
2	Based on the configuration file.

Return

int[]	Return data in an integer array.

Syntax 2

int[] **cclink_read_output_int**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as syntax 1. Fill 2 as the last parameter int by default.

* Convert the read data to an int array based on Little Endian (DCBA) or Big Endian (ABCD).

```
int[] var_ia = cclink_read_output_int(160,12,0)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00,0x0D,0x00,0x39,0x00,0x24,0x00} (Little Endian)  to int[]
    // int[] = {0x000607E8,0x000D0019,0x00240039} (Little Endian)
    // int[] = {395240,851993,2359353}
var_ia = cclink_read_output_int(160,6,0)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00} (Little Endian) to int[]
    // int[] = {0x000607E8,0x00000019} (Little Endian)
    // int[] = {395240,25}
var_ia = cclink_read_output_int(160,1,0)
    // byte[] = {0xE8} (Little Endian)  to int[]
    // int[] = {0x000000E8} (Little Endian)
    // int[] = {232}
var_ia = cclink_read_output_int(160,12)
    // byte[] = {0xE8,0x07,0x06,0x00,0x19,0x00,0x0E,0x00,0x02,0x00,0x08,0x00 (Little Endian) to int[]
    // int[] = {0x000607E8,0x000E0019,0x00080002} (Little Endian)
    // int[] = {395240,917529,524290}
```

Syntax 3

```
int cclink_read_output_int(
    int
)
```

Parameter

int	Starting address * Convert the read data to an integer based on Little Endian (DCBA) or Big Endian (ABCD).

Return

int	Return data in an integer

Note

```
int var_i = cclink_read_output_int(160)
    // byte[] = {0xE8,0x07,0x06,0x00} (Little Endian)  to int[]
    // int[] = 0x000607E8 (Little Endian)
    // int = 395240
```

21.10 cclink_read_output_float()

Read the output table content and convert the data to the 32-bit floating-point number.

Syntax 1

float[] **cclink_read_output_float**(
int,
int,
int
)

Parameter

int	Starting address
int	The address amount to read
int	The conversion of the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD). 0 Little-Endian 1 Big-Endian 2 Based on the configuration file.

Return

float[]	Return data in a floating-point number array.

Syntax 2

float[] **cclink_read_output_float**(
int,
int
)

Parameter

int	Starting address
int	The address amount to read

Note

Same as syntax 1. Fill 2 as the last parameter int by default.

*Convert the read data to a float array based on Little Endian (DCBA) or Big Endian (ABCD).

```
float[] var_fa = cclink_read_output_float(256,24,0)
    // byte[] =
    {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little
    Endian)
    // float[] = {0.01,-252.6,891.7,90,0,0}
var_fa = cclink_read_output_float(256,12,0)
    // byte[] = {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44 } (Little Endian)  to
    float[]
    // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD} (Little Endian)
    // float[] = {0.01,-252.6,891.7}
var_fa = cclink_read_output_float(256,2,0)
    // byte[] = {0x0A,0xD7} (Little Endian) to float[]
```

```
        // float[] = {0x0000D70A} (Little Endian)
        // float[] = {0}
    var_fa = cclink_read_output_float(256,24)
        // byte[] =
        {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44,0x00,0x00,0xB4,0x42,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
        // float[] = {0x3C23D70A,0xC37C999A,0x445EECCD,0x42B40000,0x00000000,0x00000000} (Little
        Endian)
        // float[] = {0.01,-252.6,891.7,90,0,0}
```

Syntax 3

```
float cclink_read_output_float(
    int
)
```

Parameter

int	Starting address *Convert the read data to a floating-point number based on Little Endian (DCBA) or Big

Return

float	Return data in a floating-point number

Note

```
float var_f = cclink_read_output_float(256)
    // byte[] = {0x0A,0xD7,0x23,0x3C} (Little Endian) to float[]
    // float[] = 0x3C23D70A (Little Endian)
    // float = 0.01
```

21.11 cclink_read_output_string()

Read the output table content and convert the data to the string encoded in UTF8.

Syntax 1

```
string cclink_read_output_string(
    int,
    int
)
```

Parameter

int	Starting address
int	The address amount to read

Return

string	Return data in a UTF8 string (ending with 0x00 encountered).

Note

```
string var_s = cclink_read_output_string(172,32)
    // byte[] = {0x63,0x63,0x6C,0x69,0x6E,0x6B,0x5F,0x66,0x75,0x6E,0x63,0x00,0x00,0x00,0x00,0x00,
    0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = "cclink_func"
var_s = cclink_read_output_string(172,3)
    // byte[] = {0x0A,0xD7,0x23,0x3C,0x9A,0x99,0x7C,0xC3,0xCD,0xEC,0x5E,0x44 }
    // string = " ccl"
```

21.12 cclink_read_output_bit()

Read the output table content and retrieve the nth bit value of the data byte.

Syntax 1

byte **cclink_read_output_bit**(
    int,
    int
)

Parameter

int	Starting address
int	The nth bit value in the data byte

Return

Byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = cclink_read_output_bit(6,0)
    // byte[] = {0xEE}
    // 0
var_b = cclink_read_output_bit(6,7)
    // byte[] = {0xEE}
    // 1
var_b = cclink_read_output_bit(6,15)
    // byte[] = {0x66}
    // 0
```

Syntax 2

byte **cclink_read_output_bit**(
    string,
    int
)

Parameter

string	Item name
int	The nth bit value

Return

byte	Return data in byte. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte.

Note

```
byte var_b = cclink_read_output_bit("CtrlBox_DO",0)
    // byte[] = {0xEE}
    // 0
var_b = cclink_read_output_bit("CtrlBox_DO",7)
    // byte[] = {0xEE}
    // 1
```

```
var_b = cclink_read_output_bit("CtrlBox_DO",15)
    // byte[] = {0x66}
    // 0
```

Syntax 3

```
byte[] cclink_read_output_bit(
    int,
    int,
    int
)
```

Parameter

int	Starting address
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = cclink_read_output_bit(6,0,16)
    // byte[] = {0xEE,0x66}
    // byte[] = {0,1,1,1,0,1,1,1,0,1,1,0,0,1,1,0}
var_ba = cclink_read_output_bit (6,8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = cclink_read_output_bit (6,6,4)
    // byte[] = {0xEE,0x66}
    // byte[] = {1,1,0,1}
```

Syntax 4

```
byte[] cclink_read_output_bit(
    string,
    int,
    int
)
```

Parameter

string	Item name
int	Starting bit
int	The amount of bit to read

Return

byte[]	Return data in byte[]. Return 1 for bit value == 1. Return 0 for bit value == 0. *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Note

```
byte[] var_ba = cclink_read_output_bit("CtrlBox_DO",0,16)
    // byte[] = {0xEE,0x66}
```

```
    // byte[] = {0,1,1,1,0,1,1,1,0,1,1,0,0,1,1,0}
var_ba = cclink_read_output_bit ("CtrlBox_DO",8,4)
    // byte[] = {0x66}
    // byte[] = {0,1,1,0}
var_ba = cclink_read_output_bit ("CtrlBox_DO",6,4)
    // byte[] = {0xEE,0x66}
    // byte[] = {1,1,0,1}
```

21.13 cclink_write_output()

Write data to the output table.

Syntax 1

bool **cclink_write_output**(
int,
?,
int
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	The maximum amount of the address to write	
	> 0	Valid data length. Write by the amount of the address.
	<= 0	Invalid data length. Write by the complete length of the data to write.

Return

Bool	True	Write successfully.
	False	Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 2

bool **cclink_write_output**(
int,
?
)

Parameter

int	Starting address	
?	The data to write	
	* Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	

Return

Bool	True	Write successfully.
	False	Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 1. Write with the full length of the data to write by default.
* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 3

bool **cclink_write_output**(

int,
?,
int,
int
)

Parameter

int	Starting address
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**
int	Starting address of the data to write
int	The amount of the address to write

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

** Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
byte var_data = 255
cclink_write_output(12,var_data,1)
byte var_b = cclink_read_output(12)
    // 0xFF

byte[] var_data = {1,127,255}
cclink_write_output(12,var_data,2)
byte[] var_ba = cclink_read_output(12,3)
    // {0x01,0x7F,0x00}
cclink_write_output(12,var_data,3)
var_ba = cclink_read_output(12,3)
    // {0x01,0x7F,0xFF}
cclink_write_output(12,var_data,-1)
var_ba = cclink_read_output(12,3)
    // {0x01,0x7F,0xFF}

int var_data = 32767
cclink_write_output(12,var_data,4)
var_i = cclink_read_output_int(12)
    // byte[] = {0xFF,0x7F,0x00,0x00} (Little Endian) to int
    // int = 0x00007FFF (Little Endian)
    // int = 32767
cclink_write_output(12,var_data,1)
var_i = cclink_read_output_int(12)
    // byte[] = {0xFF,0x00,0x00,0x00} (Little Endian) to int
    // int = 0x000000FF (Little Endian)
    // int = 255
```

```
int[] var_data = {32767,99999,-32768}
cclink_write_output(12,var_data,12)
int[] var_ia = cclink_read_output_int(12,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
cclink_write_output(12,var_data,3)
var_ia = cclink_read_output_int(12,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x00000000,0x00000000} (Little Endian)
    // int[] = {32767,0,0}
cclink_write_output(12,var_data,4,4)
var_ia = cclink_read_output_int(12,12)
    // byte[] = {0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x0001869F,0x00000000,0x00000000} (Little Endian)
    // int[] = {99999,0,0 }

float var_data = -10.0
cclink_write_output(12,var_data,4)
float var_f = cclink_read_output_float(12)
    // byte[] = {0x00,0x00,0x20,0xC1} (Little Endian) to float
    // float = 0xC1200000 (Little Endian)
    // float = -10.0
cclink_write_output(12,var_data,1)
var_f = cclink_read_output_int(12)
    // byte[] = {0x00,0x00,0x00,0x00} (Little Endian) to float
    // float = 0x00000000 (Little Endian)
    // float = 0

float[] var_data = {-10.0,3.3,123.45}
cclink_write_output(12,var_data,12)
float[] var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10.0,3.3,123.45}
cclink_write_output(12,var_data,3)
var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x00,0x00,0x20,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x00200000,0x00000000,0x00000000} (Little Endian)
    // float[] = {0,0,0}
cclink_write_output(12,var_data,4,4)
var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x33,0x33,0x53,0x40,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00} (Little Endian) to float[]
    // float[] = {0x40533333,0x00000000,0x00000000} (Little Endian)
    // float[] = {3.3,0,0}

string var_data = "abcdefg1234567"
cclink_write_output(12,var_data,16)
```

```
string var_s = cclink_read_output_string(12,32)
    // byte[] = {0x61,0x62,0x63,0x64,0x65,0x66,0x67,0x31,0x32,0x33,0x34,0x35,0x36,0x37,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = abcdefg1234567
cclink_write_output(12,var_data,8)
var_s = cclink_read_output_string(12,32)
    // byte[] = {0x61,0x62,0x63,0x64,0x65,0x66,0x67,0x31,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = abcdefg1
cclink_write_output(12,var_data,3,3)
var_s = cclink_read_output_string(12,32)
    // byte[] = {0x64,0x65,0x66,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,
        0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00}
    // string = def
```

Syntax 4

```
bool cclink_write_output(
    string,
    int,
    ?,
    int,
    int
)
```

Parameter

string	Item name
int	The starting shifted address of the item
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**
int	Starting address of the data to write
int	The amount of the address to write

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 5

```
bool cclink_write_output(
    string,
    int,
    ?,
    int
)
```

Parameter

string	Item name
int	The starting shifted address of the item

?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**	
int	Starting address of the data to write	

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 4. Write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 6

bool **cclink_write_output**(
string,
int,
?
)

Parameter

string	Item name
int	The starting shifted address of the item
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool	True	Write successfully.
	False	Write unsuccessfully. 1. If the data to write is an empty string or an empty array 2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting address to write and write with the full length of the data to write by default.

* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

Syntax 7

bool **cclink_write_output**(
string,
?
)

Parameter

string	Item name
?	The data to write * Available data types include **byte**,**byte[]**,**int**,**int[]**,**float**,**float[]**,**string**

Return

bool	True	Write successfully.
	False	Write unsuccessfully.

1. If the data to write is an empty string or an empty array
2. Unable to send and receive correctly.

Note

Same as syntax 4. Fill 0 as the starting shifted address and the starting address to write as well as write with the full length of the data to write by default.
* Write data based on Little Endian (DCBA) or Big Endian (ABCD) in the configuration file.

```
int[] var_data = {32767,99999,-32768}
cclink_write_output("Register_1",0,var_data,0,12)
int[] var_ia = cclink_read_output_int(12,12)
    // byte[] = {0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x80,0xFF,0xFF} (Little Endian) to int[]
    // int[] = {0x00007FFF,0x0001869F,0xFFFF8000} (Little Endian)
    // int[] = {32767,99999,-32768}
cclink_write_output("Register_1",4,var_data,4,4)
var_ia = cclink_read_output_int(12,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x9F,0x86,0x01,0x00,0x00,0x00,0x00,0x00} (Little Endian) to int[]
    // int[] = {0x00000000,0x0001869F,0x00000000} (Little Endian)
    // int[] = {0,99999,0}
cclink_write_output("Register_1",4,var_data)
var_ia = cclink_read_output_int(12,12)
    // byte[] = {0x00,0x00,0x00,0x00,0xFF,0x7F,0x00,0x00,0x9F,0x86,0x01,0x00} (Little Endian) to int[]
    // int[] = {0x00000000,0x00007FFF,0x0001869F} (Little Endian)
    // int[] = {0,32767,99999}

float[] var_data = {-10.0,3.3,123.45}
cclink_write_output("Register_1",0,var_data,0,12)
float[] var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x00,0x00,0x20,0xC1,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0xC1200000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {-10.0,3.3,123.45}
cclink_write_output("Register_1",4,var_data,4,8)
var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x33,0x33,0x53,0x40,0x66,0xE6,0xF6,0x42} (Little Endian) to float[]
    // float[] = {0x00000000,0x40533333,0x42F6E666} (Little Endian)
    // float[] = {0,3.3,123.45}
cclink_write_output("Register_1",8,var_data)
var_fa = cclink_read_output_float(12,12)
    // byte[] = {0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x00,0x20,0xC1} (Little Endian) to float[]
    // float[] = {0x00000000,0x00000000,0xC1200000} (Little Endian)
    // float[] = {0,0,-10}
```

21.14 cclink_write_output_bit()

Write content to the nth bit value of the data byte in the output table.

Syntax 1

```
bool cclink_write_output_bit(
    int,
    int,
    int
)
```

Parameter

int	Starting address	
int	The nth bit value	
int	The data to write *Data in bit will write in int.	

Return

Bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive .

Note

```
byte var_data = 240
cclink_write_output(12,var_data)
byte var_b = cclink_read_output(12)
    // 0xF0
cclink_write_output_bit(12,1,1)
var_b = cclink_read_output_bit(12,1)
    // 0xF2      get bit: "1"
    // 1
cclink_write_output_bit(12,7,0)
var_b = cclink_read_output_bit(12,7)
    // 0x72      get bit: "7"
    // 0
```

Syntax 2

```
bool cclink_write_output_bit(
    string,
    int,
    int
)
```

Parameter

string	Item name
int	The nth bit value
int	The data to write *Data in bit will write in int.

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

```
byte var_data = 240
cclink_write_output(12,var_data)
byte var_b = cclink_read_output(12)
    // 0xF0
cclink_write_output_bit("Register_1",1,1)
var_b = cclink_read_output_bit(12,1)
    // 0xF2      get bit: "1"
    // 1
cclink_write_output_bit("Register_1",7,0)
var_b = cclink_read_output_bit(12,7)
    // 0x72      get bit: "7"
    // 0
```

Syntax 3

bool **cclink_write_output_bit**(
int,
int,
byte[],
int,
int
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit of the data to write	
int	The bit amount of the data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 4

bool **cclink_write_output_bit**(
int,
int,
byte[],
int
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit of the data to write	

Return

Bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 3. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 5

bool **cclink_write_output_bit**(
int,
int,
byte[]
)

Parameter

int	Starting address	
int	The nth bit value	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 3. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
cclink_write_output_bit(12,0,var_data,0,20)
byte[] var_ba = cclink_read_output(12,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = cclink_read_output_bit (12,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
cclink_write_output_bit(12,3,var_data,5,10)
var_ba = cclink_read_output (12,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = cclink_read_output_bit (12,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

Syntax 6

```
bool cclink_write_output_bit(
    string,
    int,
    byte[],
    int,
    int
)
```

Parameter

string	Item name	
int	Starting bit	
byte[]	The data to write	
	*Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].	
int	The starting bit to write data	
int	The bit amount of the data to write	

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 7

bool **cclink_write_output_bit**(
string,
int,
byte[],
int
)

Parameter

string	Item name
int	Starting bit
byte[]	The data to write *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].
int	The starting bit to write data

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 6. Write with the full length of the rest data to write.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

Syntax 8

bool **cclink_write_output_bit**(
string,
int,
byte[]
)

Parameter

string	Item name
int	Starting bit
byte[]	The data to write *Data in bit will return in byte such as bit[0] for byte[0] and bit[1] for byte[1].

Return

bool	True	Write successfully.	
	False	Write unsuccessfully.	1. Unable to send correctly and receive.

Note

*Same as syntax 6. Fill 0 as the starting bit to write as well as write with the full length of the data to write by default.
Bit value = 1 for byte value >=1
Bit value = 0 for byte value ==0

```
byte[] var_data = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
cclink_write_output_bit("Register_1",0,var_data,0,20)
byte[] var_ba = cclink_read_output(12,3)
    // byte[] = {0x39,0xB8,0x0C}
var_ba = cclink_read_output_bit (12,0,20)
    // byte[] = {1,0,0,1,1,1,0,0,0,0,0,1,1,1,0,1,0,0,1,1}
cclink_write_output_bit("Register_1",3,var_data,5,10)
```

```
var_ba = cclink_read_output (12,3)
    // byte[] = {0x08,0x0E,0x00}
var_ba = cclink_read_output_bit (12,0,20)
    // byte[] = {0,0,0,1,0,0,0,0,0,1,1,1,0,0,0,0,0,0,0,0}
```

22. Real-Time Remote Server

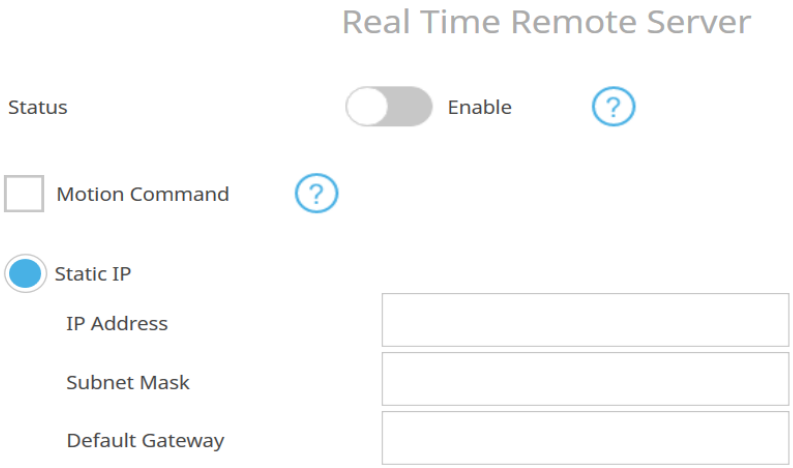
Real-Time Remote Server (RTRS) comes with functions established with Socket TCP based on the framework of client/server connections. Once enabled, the robot establishes a Real-Time Socket TCP Listening Server to send the robot status and data to all of the connected clients or receive the contents from the clients to execute the respective instructions and update the respective information periodically and promptly without the real-time guarantee.

When the TMflow program starts, the Real-Time Remote Server either launches automatically or stays inactive, depending on the configured settings. It shuts down only when the TMflow program is closed or when explicitly configured to stop. The server's IP address and port number appear in the Notice Window.

IP TMflow → Configuration → Remote Control Settings → Command Interface → RTRS → Static IP

Port 5895 (TMRTS) , 5896 (TMRTC)

22.1 GUI Setting



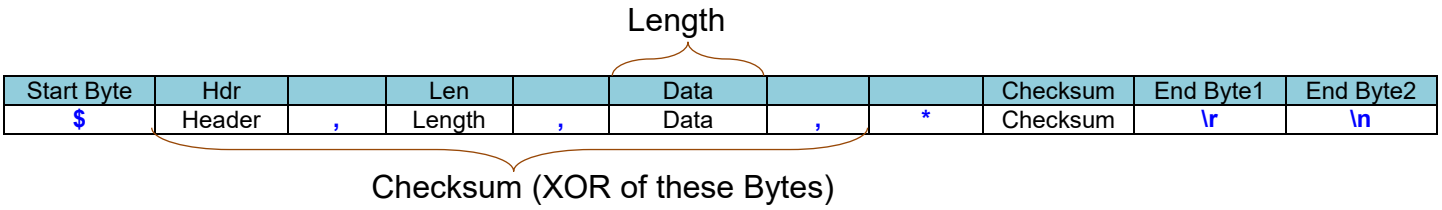
Enable/Disable Enable or disable Real-Time Remote Server. Once enabled, a system restart is required for the changes to take effect.

Motion Control Instructions Motion control commands become available once enabled, and the robot will switch to external control mode.

TMRTS Packet header for data communication manages data communication. The system activates without requiring the selection of the Motion Command option in the interface. The connection becomes available after a system restart. For detailed packet specifications, refer to the TMRTS documentation.

TMRTC Packet Header for Data Communication manages data communication. The system activates by requiring the selection of the Motion Command option in the interface. The connection becomes available after a system restart. This packet format is used solely for motion control. To obtain robot status for coordinated control, use it together with TMRTS packets. For motion control packet details, refer to the TMRTC documentation.

22.2 Communication Protocol



Name	Size	ASCII	HEX	Description
Start Byte	1	$	0x24	Start Byte for Communication
Header	*X*			Header for Communication
Separator	1	,	0x2C	Separator between Header and Length
Length	*Y*			Length of Data
Separator	1	,	0x2C	Separator between Length and Data
Data	*Z*			Communication Data
Separator	1	,	0x2C	Separator between Data and Checksum
Sign	1	*	0x2A	Begin Sign of Checksum
Checksum	*2*			Checksum of Communication
End Byte 1	1	\r	0x0D	
End Byte 2	1	\n	0x0A	End Byte of Communication

*Using the same communication protocol with external commands.

1. Header

Defines the purpose of communication packets. Different headers come with different definitions of communication packets and data.

- *TMRTS* Defines the data transmission functions of TM Real-Time Remote Server
- *TMRTC* Defines the motion control functions of TM Real-Time Remote Server
- *CPERR* Defines the errors of the communication packets such as packer errors, checksum errors, header errors, and so on.
  *Using the same content definitions with CPERR in external commands.

2. *Length*

The length indicates the length in the UTF8 bytes occupied by Data. Users can use decimal, hexadecimal, or binary format. The maximum length is 32 bits.

For example,

```
$TMRTS,100,Data,*CS\r\n          // 100 in decimal indicates the data length is 100 bytes
$TMRTS,0x100,Data,*CS\r\n        // 0x100 in hexadecimal indicates the data length is 256 bytes
$TMRTS,0b100,Data,*CS\r\n        // 0b100 in binary indicates the data length is 4 bytes
$TMRTS,8,1,達明,*CS\r\n          // indicates the length of Data,  1,達明, is 8 bytes (UTF8)
```

3. *Data*

The communication packet can contain any characters (0x00–0xFF, using UTF-8 encoding), with the data length determined by the Length field. The purpose and description of the Data must follow the Header definition.

4. *Checksum*

The checksum of the communication packet. The calculation method is XOR (exclusive OR). The calculation range is all Bytes between $ and * (excluding $ and *) as shown below.

$TMRTS,100,Data,*CS\r\n

Checksum = Byte[1] ^ Byte[2] … ^ Byte[N-6]

The checksum format is set to 2 bytes in hexadecimal (but not 0x), such as

$TMRTS,5,10,OK,*7C

CS = 0x54 ^ 0x4D ^ 0x52 ^ 0x54 ^ 0x53 ^ 0x2C ^ 0x35 ^ 0x2C ^ 0x31 ^ 0x30 ^ 0x2C ^ 0x4F ^ 0x4B ^ 0x2C = 0x7C

CS = 7C (0x37 0x43)

22.3 TMRTS

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*TMRTS*	,	Length	,	Data	,	*	Checksum	\r	\n

ID			Mode		Content
Transaction ID		,	0/1/ 7/8/9	,	Item or Value

TMRTS is defined as the communication protocol used on port 5895 in the Real-Time Remote Server (RTRS). The Data section of the packet is further divided into three segments, ID (Transaction ID), Mode (Content Mode), and Content (Item and Value), separated with commas and described below.

ID The transaction number expressed in any alphanumeric characters. (Reports the CPERR 04 error if a non-alphanumeric byte is encountered.) When used as a communication packet response, it is a transaction number that identifies which group of commands to respond.

, The symbol to separate

Mode The data format and structure define the type of content transmitted.

- 4 Indicates the server responds to a client command; data format is string.
- 5 Indicates either that the server sends data to the client at fixed intervals or the client sends a command to the server; data format is binary.
- 7 Initiates or stops data transmission from the server to the client.
- 8 Sets the transmission frequency (in Hz) for data sent from the server to the client.
- 9 Configures the data content transmitted from the server to the client

, The symbol to separate

Content The data content. Formatted by the mode definition.

Note

TMRTS command is for the client and the server to communicate in both directions. Under normal circumstances, the server periodically sends data to the client based on the item list configured by the client using Mode 9. When the server sends to the client, the data is sent to the client to read from the server with no response to the server required. When the client sends to the server, the data is received by the server from the client to write with response to the client required.

- ID Transaction Number

During periodic data transmission, the server increments the transmission number from 0 to 9 before restarting at 0. When the client sends data to the server, the transmission number can be defined by the client using any alphanumeric characters. After verifying the correctness of the communication packet format, the server will respond to the client's command processing status based on the transmission number within the packet.

- Mode Format and Mode for the Data Content

When Mode = 1, the client writes data to the server. The client can write multiple items in a single transmission, it is not limited to one. The server will send the command processing status information in the format of Mode 0, described in the section below.

When Mode = 8 or 9, the client configures the data transmission frequency and content. When Mode = 7, the client starts or stops data transmission. The typical usage flow is as follows:

1. Enable the RTRS service.
2. Configure the transmission frequency and data content using the TMRTS protocol, Mode 8 and Mode 9, respectively.
3. Start data transmission using TMRTS Mode 7.
4. To write data, send a command using TMRTS Mode 1.

- Writing or Reading Confirmation

When the client sends data writing to the server, the servers check whether all the criteria are correct before performing the request. If there is any error with the write command, no request will be performed. The criteria to write to the server are:

1. Data format being transmitted (Mode)
2. Whether the connected IP address has write permission (IP address with Write Permission)
3. Whether the data content conforms to the data format (Mode and Content)
4. The item to write exists.
5. The attribute of the item to write is not read only.
6. The written data matches the data type of each item.
7. Data transmission settings (Mode 9) are successfully configured.

22.3.1 Mode = 0 (the server status response to the client command processing)

After the server receives and processes a write command from a client, it will respond with another command with Mode 0. The details for Mode 0 are as follows.

Data

ID		Mode		Error Code		Error Description
Transaction ID	,	***0***	,	00 .. 08	,	

Transaction ID Defined while the client sends the command for the server to reply with.

Mode 0 for the server to respond to the client

Error Code Error code definitions. Fixed as 2 hexadecimal bytes but without 0x

- 00 Correct writing. No error.
- 01 The communication format or mode is not supported. (Ex. Mode = 99)
- 02 The connected client is not permitted to write. (IP address without write permission)
- 03 The communication format and the data content format are mismatched. (Ex Not in binary format)
- 04 Item to write does not exist.
- 05 Unable to write to read-only items.
- 07 Values to write do not match with the configured type or the size.
- 08 Incomplete data transmission configuration.

Error Description Error description, following the error code

- 00 OK
- 01 NotSupport;XXX
- 02 WritePermission
- 03 InvalidData
- 04 NotExist;XXX // ;XXX denotes which the incorrect data item
- 05 ReadOnly;XXX
- 07 ValueError;XXX
- 08 SettingIncomplete

When input is correct and the server responds

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    35 2C                  // 5,           // Length
    32 2C 37 2C            // 2,7,         // transaction ID 2, mode 7
    30                     // 0            // Close data transmission
    2C 2A 36 30 0D 0A      // ,*60\r\n     // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    39 2C                  // 9,           // Length
    32 2C 30 2C            // 2,0,         // server responds to ID 2, mode 0
    30 30 2C               // 00,          // Error Code 00
    4F 4B                  // OK           // Correct writing
    2C 2A 37 33 0D 0A      // ,*73\r\n     // Checksum
```

When using a non-existent Mode

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    35 2C                  // 5,           // Length
    33 2C 35 2C            // 3,5,         // transaction ID 3, mode 5
    30                     // 0
    2C 2A 36 33 0D 0A      // ,*63\r\n     // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    32 30 2C               // 20,          // Length
    33 2C 30 2C            // 3,0,         // server responds to ID 30, mode 0
    30 31 2C               // 01,          // Error Code 01
    4E 6F 74 53 75 70 70 6F 72 74 3B 20 35   // NotSupport; 5   // mode 5 not supported
    2C 2A 37 38 0D 0A      // ,*78\r\n     // Checksum
```

When multiple clients write to the same item simultaneously, all writes will occur on the first client if a client without write permission issues a write command.

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    31 37 2C               // 17,          // Length
    31 2C 31 2C            // 1,1,         // transaction ID 1, mode 1
    08 00 43 74 72 6C 5F 44 4F 31 01 00 01   // Ctrl_DO1=1
                                             // The name occupied 8 bytes, the value, 1 byte
    2C 2A 32 32 0D 0A      // ,*22\r\n     // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    32 32 2C               // 22,          // Length
    31 2C 30 2C            // 1,0,         // server responds to ID 1, mode 0
    30 32 2C               // 02,          // Error Code 02
    57 72 69 74 65 50 65 72 6D 69 73 73 69 6F 6E   // WritePermission   // No writing permission
    2C 2A 33 39 0D 0A      // ,*39\r\n     // Checksum
```

When the data content is invalid

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    31 37 2C               // 17,          // Length
    33 32 2C 39 2C         // 32,9,        // transaction ID 32, mode 9
    0B 00 4A 6F 69 6E 74 41 6E 67 6C 65   // JointAngle
```

```
                                                    // The name occupied 11 bytes, and 10 bytes, actually
      2C 2A 34 32 0D 0A          // ,*42\r\n       // Checksum
>     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      31 39 2C                   // 19,            // Length
      33 32 2C 30 2C             // 32,0,          // server responds to ID 32, mode 0
      30 33 2C                   // 03,            // Error Code 03
      49 6E 76 61 6C 69 64 44 61 74 61           // InvalidData   // Incorrect number of bytes used for
                                                                   the item name.
      2C 2A 31 37 0D 0A          // ,*17\r\n       // Checksum
```

When attempting to configure a non-existent item as a data exchange target

```
<     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      37 2C                      // 7,             // Length
      30 2C 39 2C                // 0,9,           // transaction ID 0, mode 9
      01 00 30                   // 0              // The name occupied 1 byte
      2C 2A 36 46 0D 0A          // ,*6F\r\n       // Checksum
>     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      31 37 2C                   // 17,            // Length
      30 2C 30 2C                // 0,0,           // server responds to ID 0, mode 0
      30 34 2C                   // 04,            // Error Code 04
      4E 6F 74 45 78 69 73 74 3B 30              // NotExist;0    // Item 0 does not exist.
      2C 2A 34 33 0D 0A          // ,*43\r\n       // Checksum
```

When the client writes a value to a read-only item

```
<     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      31 37 2C                   // 17,            // Length
      32 37 2C 31 2C             // 27,1,          // transaction ID 27, mode 1
      07 00 45 6E 64 5F 44 49 30 01 00 01        // End_DI0=1
                                                    // The name occupied 7 bytes, the value, 1 byte
      2C 2A 37 38 0D 0A          // ,*78\r\n       // Checksum
>     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      32 34 2C                   // 24,            // Length
      32 37 2C 30 2C             // 27,0,          // server responds to ID 27, mode 0
      30 35 2C                   // 05,            // Error Code 05
      52 65 61 64 4F 6E 6C 79 3B 45 6E 64 5F 44 49 30    // ReadOnly;End_DI0
                                                          //Read-only access only.
      2C 2A 36 41 0D 0A          // ,*6A\r\n       // Checksum
```

When the value in the client's command exceeds the allowable range

```
<     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      39 2C                      // 9,             // Length
      33 30 2C 38 2C             // 30,8,          // transaction ID 30, mode 8
      00 00 16 44                // 600            // Floating-point number
      2C 2A 33 30 0D 0A          // ,*30\r\n       // Checksum
>     24 54 4D 52 54 53 2C       // $TMRTS,        // Header
      34 34 2C                   // 44,            // Length
```

```
33 30 2C 30 2C          // 30,0,          // server responds to ID 30, mode 0
30 37 2C                // 07,            // Error Code 07
56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6F 75 74 20 6F
66 20 72 61 6E 67 65    // ValueError;The value is out of range      // Value out of range
2C 2A 34 30 0D 0A       // ,*40\r\n       // Checksum
```

When the client attempts to start data transmission without completing the data exchange item configuration

```
<  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   35 2C                   // 5,             // Length
   31 2C 37 2C             // 1,7,           // transaction ID 1, mode 7
   31                      // 1              // Open data transmission
   2C 2A 36 32 0D 0A       // ,*62\r\n       // Checksum
>  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   32 34 2C                // 24,            // Length
   31 2C 30 2C             // 1,0,           // server responds to ID 1, mode 0
   30 38 2C                // 08,            // Error Code 08
   53 65 74 74 69 6E 67 49 6E 63 6F 6D 70 6C 65 74 65// SettingIncomplete
                                              // Configuration incomplete.
   2C 2A 33 42 0D 0A       // ,*3B\r\n       // Checksum
```

Assume the Client sets the read-only data in the server

```
<  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   31 38 2C                // 18,            // Length
   32 32 2C 31 2C          // 22,1,          // transaction ID 22, mode 1, binary
   08 00 43 74 72 6C 5F 44 49 30 01 00 01    // Ctrl_DI0=1
                                              // The name occupied 8 bytes, the value, 1 byte
   2C 2A 31 42 0D 0A       // ,*1B\r\n       // Checksum
>  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   32 35 2C                // 25,            // Length
   32 32 2C 30 2C          // 22,0,          // server responds to ID 22, mode 0
   30 35 2C                // 05,            // error code 05
   52 65 61 64 4F 6E 6C 79 3B 43 74 72 6C 5F 44 49 30        // ReadOnly;Ctrl_DI0
                                              // Read-only access only
   2C 2A 30 38 0D 0A       // ,*08\r\n       // Checksum
```

Assume the data name length setting is incorrect when configuring the server from the client

```
<  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   31 37 2C                // 17,            // Length
   32 2C 31 2C             // 2,1,           // transaction ID 2, mode 1, binary
   00 00 43 74 72 6C 5F 44 4F 30 01 00 01    // Ctrl_DI0=1
                                              // The name occupied 0 byte (error), the value, 1 byte
   2C 2A 32 38 0D 0A       // ,*28\r\n       // Checksum
>  24 54 4D 52 54 53 2C    // $TMRTS,        // Header
   31 38 2C                // 18,            // Length
```

```
32 2C 30 2C                     // 2,0,        // server responds to ID 2, mode 0
30 33 2C                        // 03,         // error code 03
49 6E 76 61 6C 69 64 44 61 74 61                // InvalidData     // Invalid data
2C 2A 32 35 0D 0A               // ,*25\r\n    // Checksum
```

22.3.2 Mode = 1 BINARY

The system transmits data in binary format, converting item names and values into byte arrays: numeric values use Little Endian format, and string values use UTF-8 encoding. The table below shows the format. Mode 1 acts as the server regularly sends predefined data items to one or more clients, or when a client writes values to writable data items on the server. When multiple clients are connected, write access is granted to the first client that writes to a data exchange item. Due to the high frequency of data exchange, the server may not respond correctly if the client issues the correct command.

Data

ID		Mode		Content
Transaction ID	,	1	,	Item and Value

Length of Item *2 bytes Little Endian*	***Item*** *UTF8*	***Length of Value*** *2 bytes Little Endian*	***Value*** *Little Endian / UTF8*	...

Length of Item 2 bytes in Little Endian, value from 0 to 65535 indicating the length of the item that follows
Item item name
Length of Value 2 bytes in Little Endian, value from 0 to 65535 indicating the length of the data value that follows
Value data value

Assume the communication data includes Joint_Angle (type: float[]) transmitted from the Server to the Client.

```
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    34 33 2C               // 43,          // Length
    30 2C 31 2C            // 0,1,         // transaction ID 0, mode 1, binary
    0B 00 4A 6F 69 6E 74 5F 41 6E 67 6C 65 18 00 3C BD 2D 41 3F F7 14 C3 77 ED 36 42 AB
    FE 0F 43 78 FA 95 41 4F 6F 07 42
                           //Joint_Angle={10.8587, -148.9658, 45.7319, 143.9948,
                           18.7473, 33.8587}
                           // The name occupied 11 bytes, the value, 24 bytes
    2C 2A 30 42 0D 0A      // ,*0B\r\n     // Checksum
```

Assume the Client sets the values of Ctrl_DO2 (type: byte) and Ctrl_AO0 (type: float). Note that in this case, the Server will not respond to the Client.

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    34 31 2C               // 41,          // Length
    31 2C 31 2C            // 1,1,         // transaction ID 1, mode 1, binary
    08 00 43 74 72 6C 5F 44 4F 32 01 00 01          // Ctrl_DO2=1
                                                    // The name occupied 8 bytes, the value, 1 byte
    08 00 43 74 72 6C 5F 41 4F 30 04 00 00 00 80 3F // Ctrl_AO0=1
                                                    // The name occupied 8 bytes, the value, 4
                                                    bytes
    2C 2A 44 39 0D 0A      // ,*D9\r\n     // Checksum
```

Assume the Client sets the read-only data in the server

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    31 38 2C               // 18,          // Length
    32 32 2C 31 2C         // 22,1,        // transaction ID 22, mode 1, binary
    08 00 43 74 72 6C 5F 44 49 30 01 00 01   // Ctrl_DI0=1
                                             // The name occupied 8 bytes, the value, 1 byte
    2C 2A 31 42 0D 0A      // ,*1B\r\n     // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    32 35 2C               // 25,          // Length
    32 32 2C 30 2C         // 22,0,        // server responds to ID 22, mode 0
    30 35 2C               // 05,          // error code 05
    52 65 61 64 4F 6E 6C 79 3B 43 74 72 6C 5F 44 49 30   // ReadOnly;Ctrl_DI0
                                                         // Read-only access only
    2C 2A 30 38 0D 0A      // ,*08\r\n     // Checksum
```

Assume the data name length setting is incorrect when configuring the server from the client

```
<   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    31 37 2C               // 17,          // Length
    32 2C 31 2C            // 2,1,         // transaction ID 2, mode 1, binary
    00 00 43 74 72 6C 5F 44 4F 30 01 00 01   // Ctrl_DI0=1
                                             // The name occupied 0 byte (error), the value, 1 byte
    2C 2A 32 38 0D 0A      // ,*28\r\n     // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,      // Header
    31 38 2C               // 18,          // Length
    32 2C 30 2C            // 2,0,         // server responds to ID 2, mode 0
    30 33 2C               // 03,          // error code 03
    49 6E 76 61 6C 69 64 44 61 74 61   // InvalidData   // Invalid data
    2C 2A 32 35 0D 0A      // ,*25\r\n     // Checksum
```

22.3.3 Mode = 7 START/STOP Data Streaming

The system transmits content in UTF-8 format to configure the start or stop of data transmission.

The table below provides a detailed outline of the format.

Data

ID		Mode		Content
Transaction ID	,	7	,	Value

UTF8
'0': STOP
'1': START

To start data transmission

```
<   24 54 4D 52 54 53 2C   // $TMRTS,   // Header
    35 2C                  // 5,        // Length
    32 2C 37 2C            // 2,7,      // transaction ID 2,7
    31                     // 1         // Start data transmission
    2C 2A 36 31 0D 0A      // ,*61\r\n  // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,   // Header
    39 2C                  // 9,        // Length
    32 2C 30 2C            // 2,0,      // server responds to ID 2, mode 0
    30 30 2C               // 00,       // Error Code 00
    4F 4B                  // OK        // Correct writing
    2C 2A 37 33 0D 0A      // ,*73\r\n  // Checksum
```

To enable the streaming function before completing the data transmission settings (Mode 9)

```
<   24 54 4D 52 54 53 2C   // $TMRTS,   // Header
    35 2C                  // 5,        // Length
    31 2C 37 2C            // 1,7,      // transaction ID 1, mode 7, binary
    31                     // 1         // Activate data transmission
    2C 2A 36 32 0D 0A      // ,*62\r\n  // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,   // Header
    32 34 2C               // 24,       // Length
    31 2C 30 2C            // 1,0,      // server responds to ID 1, mode 0
    30 38 2C               // 08,       // Error Code 08
    53 65 74 74 69 6E 67 49 6E 63 6F 6D 70 6C 65 74 65
                           // SettingIncomplete
                           // Response for incomplete data transmission settings (Mode 9)
    2C 2A 33 42 0D 0A      // ,*3B\r\n  // Checksum
```

22.3.4 Mode = 8 SET Streaming Frequency

The system transmits data in binary format at a default frequency of 50 Hz. The system converts the frequency and rounds it to the nearest whole millisecond. The server then transmits the data at the specified frequency. The table below provides a detailed outline of the format.

Data

ID		Mode		Content
Transaction ID	,	8	,	Value

float Little Endian
50-500 (Hz)

To configure the streaming transmission frequency

```
<   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    38 2C                  // 8,               // Length
    32 2C 38 2C            // 2,8,             // transaction ID 2, mode 8
    00 00 48 42            // 50               // Set transmission frequency to 50 Hz.
    2C 2A 35 38 0D 0A      // ,*58\r\n         // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    39 2C                  // 9,               // Length
    32 2C 30 2C            // 2,0,             // server responds to ID 2, mode 0
    30 30 2C 4F 4B         // 00,OK            // Error Code 00，Correct writing
    2C 2A 37 33 0D 0A      // ,*73\r\n         // Checksum

<   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    38 2C                  // 8,               // Length
    33 2C 38 2C            // 3,8,             // transaction ID 3, mode 8
    00 00 7A 44            // 1000             // Set transmission frequency to 1000Hz
    2C 2A 36 44 0D 0A      // ,*6D\r\n         // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    34 33 2C               // 43,              // Length
    33 2C 30 2C            // 3,0,             // transaction ID 3mode 0
    30 37 2C               // 07,              // Error Code 07
    56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6F 75 74 20 6F
    66 20 72 61 6E 67 65                    // ValueError;The value is out of range
                                            // The configured value exceeds the limit.
    2C 2A 37 37 0D 0A      // ,*77\r\n         // Checksum
```

22.3.5 Mode = 9 SET Streaming Data

The system transmits data content using a binary format. Configure the names of the data items to be transmitted periodically using the format shown in the table below.

Data (client to server)

ID		Mode		Content
Transaction ID	,	9	,	Item

Length of Item *2 bytes Little Endian*	***Item*** *UTF8*	...

Configure the data item without requiring a Value field, unlike Mode = 1.

Length of Item	Present the item name length using 2 bytes in Little Endian format. The value ranges from 0 to 65535 and indicates the length of the following item name.
Item	The name of the item.

To configure Joint_Angle as the data content that the server periodically sends to the client,

```
<   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    31 37 2C               // 17,              // Length
    31 2C 39 2C            // 1,9,             // transaction ID 1, mode 9
    0B 00 4A 6F 69 6E 74 5F 41 6E 67 6C 65   // Joint_Angle   // The name occupied 11 bytes
    2C 2A 32 44 0D 0A      // ,*2D\r\n         // Checksum
>   24 54 4D 52 54 53 2C   // $TMRTS,          // Header
    39 2C                  // 9,               // Length
    31 2C 30 2C            // 1,0,             // transaction ID 1, mode 0
    30 30 2C 4F 4B         // 00,OK            // Error Code 00，Correct writing
    2C 2A 37 30 0D 0A      // ,*70\r\n         // Checksum
```

22.4 TMRTC

Start Byte	Hdr		Len		Data			Checksum	End Byte1	End Byte2
$	*TMRTC*	,	Length	,	Data	,	*	Checksum	\r	\n

ID		Mode		Content
Transaction ID	,	0/1/ 7/8	,	Item and Value

TMRTC is defined as the communication protocol used on port 5896 in the Real-Time Remote Server (RTRS). The Data section of the packet is further divided into three segments, ID (Transaction ID), Mode (Content Mode), and Content (Item and Value), separated with commas and described below.

ID The transaction number expressed in any alphanumeric characters. (Reports the CPERR 04 error if a non-alphanumeric byte is encountered.) When used as a communication packet response, it is a transaction number that identifies which group of commands to respond.

, the symbol to separate

Mode The data format and structure define the type of content transmitted.

- 0 Indicates that the server responds to a command from the client as a string format
- 1 Indicates that the client sends a motion control command to the server as a binary format
- 7 Indicates to set the start or stop of the server's motion control mode
- 8 Indicates to configure the type and parameters of motion control

, the symbol to separate

Content The data content. Formatted by the mode definition.

Note

TMRTC command is for the client and the server to communicate in both directions. When the client sends a motion control setting (Mode 8) to the server, the server responds with Mode 0. However, when the client sends a motion control command (Mode 1), the server does not respond to the client.

TMRTC only allows a single client connection at a time. During motion execution, the server continuously receives motion commands from the client. If an unexpected disconnection occurs during this process, the server may remain in a state of waiting for further commands. In such cases, rebooting the robot arm is required.

- ID Transaction Number

TMRTC, unlike TMRTS, does not perform periodic data transmission. It only responds to the client when receiving a motion control setting command (Mode 8). Therefore, all transmission IDs are user-defined alphanumeric strings assigned by the client. After verifying that the packet format is correct, the server uses the transmission ID in the packet to reply with the command processing status.

- Mode Format and Mode for the Data Content

When Mode = 8, the client configures the server's motion control settings, and the server must respond using Mode 0 to acknowledge the configuration. When Mode = 1, the client sends motion control values to the server, and the server does not respond using Mode 0.

When Mode = 7, the client sets the server to start or stop motion control mode. The typical usage flow is as follows:

1. Enable the RTRS service and check motion control instructions.
2. Connect to port 5895 (TMRTS) and retrieve the robot status.
3. Connect to port 5896 (TMRTC) and configure the motion control settings using Mode 8.
4. Enable motion control Mode 7.
5. Update the motion control target values using Mode 1.

- Writing or Reading Confirmation

When the client sends data writing to the server, the servers check whether all the criteria are correct before performing the request. If there is any error with the write command, no request will be performed. The criteria to write to the server are:

1. Data format being transmitted (Mode)
2. Whether the connected IP address has write permission (IP address with Write Permission)
3. Whether the data content conforms to the data format (Mode and Content)
4. The written data matches the data type of each item.
5. Motion control settings (Mode 8) successfully configured.
6. Whether the system is in a motion-controllable state.
7. Whether motion control (Mode 7) has started.

22.4.1 Mode = 0 (the server status response to the client command processing)

After the server receives and processes a write command from a client, it will respond with another command with Mode 0. The details for Mode 0 are as follows.

Data

ID		Mode		Error Code		Error Description
Transaction ID	,	***0***	,	00, 01, 02, 03, 07, 08, 09, 10	,	

Transaction ID	Defined while the client sends the command for the server to reply with
Mode	0 for the server to respond to the client
Error Code	Error code definitions. Fixed as 2 hexadecimal bytes but without 0x
00	Correct writing. No error.
01	The communication format or mode is not supported. (Ex. Mode = 99)
02	The connected client is not permitted to write. (IP address without write permission)
03	The communication format and the data content format are mismatched
07	Values to write do not match with the configured type or the size.
08	Incomplete motion control configuration.
09	Motion command is not permitted.
10	Motion has already started
Error Description	Error description, following the error code.
00	OK
01	NotSupport;XXX
02	WritePermission
03	InvalidData
07	ValueError;XXX
08	SettingIncomplete
09	MotionNotAllowed
10	MotionStarted

When the setting command is correct

```
<   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    35 2C                  // 5,        // Length
    31 2C 37 2C            // 1,7,      // transaction ID 1, mode 7
    30                     // 0         // Stop motion control
    2C 2A 37 33 0D 0A      // ,*73\r\n  // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    39 2C                  // 9,        // Length
    31 2C 30 2C            // 1,0,      // server responds to ID 1, mode 0
    30 30 2C               // 00,       // Error Code 00
    4F 4B                  // OK        // Correct writing
    2C 2A 36 30 0D 0A      // ,*60\r\n  // Checksum
```

When using a non-existent Mode

```
<   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    35 2C                  // 5,        // Length
    30 2C 35 2C            // 1,7,      // transaction ID 0, mode 5
    30                     // 0         //
    2C 2A 37 30 0D 0A      //,*70\r\n   // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    32 30 2C               // 20,       // Length
    30 2C 30 2C            // 0,0,      // server responds to ID 0, mode 0
    30 31 2C               // 01,       // Error Code 01
    4E 6F 74 53 75 70 70 6F 72 74 3B 20 35   // NotSupport; 5   // mode 5 not supported
    2C 2A 36 42 0D 0A      // ,*6B\r\n  // Checksum
```

When Mode 7 is activated and a Mode 8 command is subsequently issued

```
<   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    31 39 2C               // 19,       // Length
    31 31 2C 38 2C         // 11,8,     // transaction ID 11, mode 8
    53 4A F4 01 00 00 00 00 80 3F F4 01 00 00   // S J 500 1 500
                           // Position mode, Joint angle mode, Acceleration-to-max-speed time:
                           500 ms, Gain: 1, Expected command interval: 500 ms
    2C 2A 45 36 0D 0A      // ,*E6\r\n  // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    32 33 2C               // 23,       // Length
    31 31 2C 30 2C         // 11,0,     // server responds to ID 11, mode 0
    30 32 2C               // 02,       // Error Code 02
    57 72 69 74 65 50 65 72 6D 69 73 73 69 6F 6E   // WritePermission
                           // When Mode 7 is active, it is not possible to write Mode 8 settings.
    2C 2A 31 39 0D 0A      // ,*19\r\n  // Checksum
```

When the Mode is not specified

```
<   24 54 4D 52 54 43 2C   // $TMRTC,   // Header
    34 2C                  // 4,        // Length
    31 2C __ 2C            // 1,,       // transaction ID 1, no mode
```

```
        31                          // 1
        2C 2A 34 34 0D 0A           // ,*44\r\n        // Checksum
>       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        31 38 2C                    // 18,             // Length
        31 2C 30 2C                 // 1,0,            // server responds to ID 1, mode 0
        30 33 2C                    // 03,             // Error Code 03
        49 6E 76 61 6C 69 64 44 61 74 61    // InvalidData     // Invalid content
        2C 2A 33 36 0D 0A           // ,*36\r\n        // Checksum
```

If the value in the command is invalid (blank)

```
<       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        34 2C                       // 4,              // Length
        30 2C 38 2C                 // 0,8,            // transaction ID 0, mode 8
                                    //
        2C 2A 34 43 0D 0A           // ,*4C\r\n        // Checksum
>       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        34 32 2C                    // 42,             // Length
        30 2C 30 2C                 // 0,0,            // server responds to ID 0, mode 0
        30 37 2C                    // 07,             // Error Code 07
        56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6E 6F 74 20 73
        75 70 70 6F 72 74           // ValueError;The value is not support // Invalid value
        2C 2A 34 37 0D 0A           // ,*47\r\n        // Checksum
```

If the value in the command is invalid (incorrect value)

```
<       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        31 38 2C                    // 18,             // Length
        30 2C 38 2C                 // 0,8,            // transaction ID 0, mode 8
        53 56 96 00 00 00 00 00 80 3F E8 03 00 00 // S V 150 1 1000
                                    // Position mode, V mode (not supported), Acceleration-to-max-speed
                                    time: 150 ms, Gain: 1, Expected command interval: 1000 ms
        2C 2A 42 36 0D 0A           // ,*B6\r\n        // Checksum
>       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        34 32 2C                    // 42,             // Length
        30 2C 30 2C                 // 0,0,            // transaction ID 0, mode 0
        30 37 2C                    // 07,             // Error Code 07
        56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6E 6F 74 20 73
        75 70 70 6F 72 74           // ValueError;The value is not support      // Unsupported value error
        2C 2A 34 37 0D 0A           // ,*47\r\n        // Checksum
```

If the motion setting is incomplete and the client issues a start motion command (Mode 7)

```
<       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
        35 2C                       // 5,              // Length
        33 2C 37 2C                 // 3,7,            // transaction ID 3, mode 7
        31                          // 1               // Start motion control
        2C 2A 37 30 0D 0A           // ,*70\r\n        // Checksum
>       24 54 4D 52 54 43 2C        // $TMRTC,         // Header
```

```
32 34 2C                    // 24,          // Length
33 2C 30 2C                 // 3,0,         // server responds to ID 3, mode 0
30 38 2C                    // 08,          // Error Code 08
53 65 74 74 69 6E 67 49 6E 63 6F 6D 70 6C 65 74 65// SettingIncomplete
                                             // Motion control configuration incomplete
2C 2A 32 39 0D 0A           // ,*29\r\n     // Checksum
```

If a motion control command is issued before motion control is enabled

```
<  24 54 4D 52 54 43 2C     // $TMRTC,      // Header
   32 38 2C                 // 28,          // Length
   30 2C 31 2C              // 0,1,         // transaction ID 0, mode 1
   CD CC CC 3D CD CC CC 3D CD CC CC 3D CD CC CC 3D CD CC CC 3D CD CC CC 3D
   // {0.1.0.1,0.1,0.1,0.1,0.1}
   2C 2A 37 42 0D 0A        // ,*7B\r\n     // Checksum
>  24 54 4D 52 54 43 2C     // $TMRTC,      // Header
   32 33 2C                 // 23,          // Length
   30 2C 30 2C              // 0,0,         // server responds to ID 0, mode 0
   30 39 2C                 // 09,          // Error Code 09
   4D 6F 74 69 6F 6E 4E 6F 74 41 6C 6C 6F 77 65 64      // MotionNotAllowed
                                                        // Motion command not permitted
   2C 2A 36 37 0D 0A        // ,*67\r\n     // Checksum
```

If motion control has already started and the client issues a start motion command (Mode 7)

```
<  24 54 4D 52 54 43 2C     // $TMRTC,      // Header
   35 2C                    // 5,           // Length
   32 2C 37 2C              // 2,7,         // transaction ID 2, mode 7
   31                       // 1            // Start motion control
   2C 2A 37 30 0D 0A        // ,*71\r\n     // Checksum
>  24 54 4D 52 54 43 2C     // $TMRTC,      // Header
   32 30 2C                 // 20,          // Length
   32 2C 30 2C              // 2,0,         // server responds to ID 2, mode 0
   31 30 2C                 // 10,          // Error Code 10
   4D 6F 74 69 6F 6E 53 74 61 72 74 65 64   // MotionStarted    // Motion control already started
   2C 2A 32 32 0D 0A        // ,*22\r\n     // Checksum
```

22.4.2 Mode = 1 BINARY

The data content is transmitted in binary mode by converting the data item name with the Little Endian value and the value with UTF8 to a byte array accordingly. The format is shown as below.

Data

ID		Mode		Content
Transaction ID	,	1	,	Value

6 * float Little Endian

Configure motion control command values

```
<   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    32 38 2C               // 28,              // Length
    30 2C 31 2C            // 0,1,             // transaction ID 0, mode 1
    3C BD 2D 41 3F F7 14 C3 77 ED 36 42 AB FE 0F 43 78 FA 95 41 4F 6F 07 42
                           // {10.8587,-148.9658,45.7319,143.9948,18.7473,33.8587}
    2C 2A 34 44 0D 0A      // ,*4D\r\n         // Checksum
```

If the command value format is incorrect-

```
<   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    32 35 2C               // 25,              // Length
    31 32 2C 31 2C         // 12,1,            // transaction ID 12, mode 1
    00 00 C8 42 00 00 C8 42 00 00 C8 42 00 00 C8 42 00 00 C8 42
                           // {100,100,100,100,100} five values only
    2C 2A 43 46 0D 0A      // ,*CF\r\n         // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    34 30 2C               // 40,              // Length
    31 32 2C 30 2C         // 12,0,            // transaction ID 12, mode 0
    30 37 2C               // 07,              // Error Code 07
    56 61 6C 75 65 45 72 72 6F 72 3B 43 6F 6E 74 65 6E 74 4C 65 6E 67 74 68 20 69 6C 6C 65
    67 61 6C
                           // ValueError;ContentLength illegal     // Invalid content length
    2C 2A 37 37 0D 0A      // ,*77\r\n         // Checksum
```

22.4.3 Mode = 7 START/STOP Motion Control

The system transmits content in UTF-8 format to configure the start or stop of motion control. The table below provides a detailed outline of the format.

Data

ID		Mode		Content
Transaction ID	,	7	,	Value

UTF8
'0': STOP
'1': START

To activate motion control, use the example below.

```
<   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    35 2C                  // 5,               // Length
    38 2C 37 2C            // 8,7,             // transaction ID 2, mode 7, binary
    31                     // 1                // Start motion control
    2C 2A 37 42 0D 0A      // ,*7B\r\n         // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    39 2C                  // 9,               // Length
    38 2C 30 2C            // 8,0,             // transaction ID 8, mode 0
    30 30 2C               // 00,              // Error Code 0
    4F 4B                  // OK               // Correct writing
    2C 2A 36 39 0D 0A      // ,*69\r\n         // Checksum

<   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    35 2C                  // 5,               // Length
    32 2C 37 2C            // 2,7,             // transaction ID 2, mode 7, binary
    31                     // 1                // Start motion control
    2C 2A 37 31 0D 0A      // ,*71\r\n         // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,          // Header
    32 34 2C               // 24,              // Length
    32 2C 30 2C            // 2,0,             // transaction ID 2, mode 0
    30 38 2C               // 08               // Error Code 08
    53 65 74 74 69 6E 67 49 6E 63 6F 6D 70 6C 65 74 65// SettingIncomplete
                                                // Configuration incomplete.
    2C 2A 32 38 0D 0A      // ,*28\r\n         // Checksum
```

22.4.4 Mode = 8 SET Motion Control Settings

The system transmits data in binary format to define the motion control type and its parameters. For parameter definitions, refer to the Position() and Velocity() functions in the chapter on Robot Motion and Vision Tasks. The table below provides a detailed outline of the format.

Data

ID		Mode		Content
Transaction ID	,	8	,	Item and Value

Position(S) →	***Position*** 1 byte string 'S'	***Control Mode*** 1 byte string 'C' or 'T' or 'J'	***Acceleration Time*** 4 bytes int 150-2000	***Gain*** 4 bytes float 1-100	***Control Interval*** 4 bytes int >= 2

Velocity(V) →	***Velocity*** 1 byte string 'V'	***Control Mode*** 1 byte string 'C' or 'T' or 'J'	***Acceleration Time*** 4 bytes int 150-2000	***Control Interval*** 4 bytes int >= 2

To set the motion control to Position mode and Joint angle mode, acceleration time to max-speed time: 150 ms, gain value of 1, and the expected command interval of 1000 ms, use the following example:

```
<   24 54 4D 52 54 43 2C   // $TMRTC,      // Header
    31 38 2C               // 18,          // Length
    35 2C 38 2C            // 5,8,         // transaction ID 5, mode 8
    53 4A 96 00 00 00 00 00 80 3F E8 03 00 00 // S J 150 1 1000
                           // Position mode, Joint angle mode, Acceleration-to-max-speed time:
                           150 ms, Gain: 1, Expected command interval: 1000 ms
    2C 2A 41 46 0D 0A      // ,*AF\r\n     // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,      // Header
    39 2C                  // 9,           // Length
    35 2C 30 2C            // 5,0,         // transaction ID 5, mode 0
    30 30 2C               // 00,          // Error Code 00
    4F 4B                  // OK           // Correct writing
    2C 2A 36 34 0D 0A      // ,*64\r\n     // Checksum
```

If the command contains invalid values

```
<   24 54 4D 52 54 43 2C   // $TMRTC,      // Header
    31 38 2C               // 18,          // Length
    30 2C 38 2C            // 0,8,         // transaction ID 0, mode 8
    53 56 96 00 00 00 00 00 80 3F E8 03 00 00 // S V 150 1 1000
                           // Position mode, V mode (not supported), Acceleration-to-max-speed time:
                           150 ms, Gain: 1, Expected command interval: 1000 ms
    2C 2A 42 36 0D 0A      // ,*B6\r\n     // Checksum
>   24 54 4D 52 54 43 2C   // $TMRTC,      // Header
    34 32 2C               // 42,          // Length
    30 2C 30 2C            // 0,0,         // transaction ID 0, mode 0
    30 37 2C               // 07,          // Error Code 07
```

```
56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6E 6F 74 20 73
75 70 70 6F 72 74        // ValueError;The value is not support        // Unsupported value error
2C 2A 34 37 0D 0A        // ,*47\r\n        // Checksum
```

If the command contains invalid values (e.g., incorrect number of parameters)

```
<  24 54 4D 52 54 43 2C   // $TMRTC,        // Header
   31 38 2C               // 18,            // Length
   33 2C 38 2C            // 3,8,           // transaction ID 3, mode 8
   56 4A 96 00 00 00 02 00 00 00 E8 03 00 00 // V J 150 2 1000
                          // Velocity mode, J mode, acceleration to maximum speed in 150 ms,
                          expected control command interval: 2 ms, unknown parameter: 1000
   2C 2A 31 31 0D 0A      // ,*11\r\n       // Checksum
>  24 54 4D 52 54 43 2C   // $TMRTC,        // Header
   34 32 2C               // 42,            // Length
   33 2C 30 2C            // 3,0,           // transaction ID 3, mode 0
   30 37 2C               // 07,            // Error Code 07
   56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6E 6F 74 20 73
   75 70 70 6F 72 74      // ValueError;The value is not support  // Unsupported value error
   2C 2A 34 34 0D 0A      // ,*44\r\n       // Checksum
```

If the command contains invalid values (e.g., value out of range)

```
<  24 54 4D 52 54 43 2C   // $TMRTC,        // Header
   31 34 2C               // 14,            // Length
   30 2C 38 2C            // 0,8,           // transaction ID 0, mode 8
   56 4A 64 00 00 00 02 00 00 00          // V J 100 2
                          // Velocity mode, J mode, acceleration to maximum speed in 100 ms
                          (exceeds the range), expected control command interval: 2 ms
   2C 2A 30 37 0D 0A      // ,*07\r\n       // Checksum
>  24 54 4D 52 54 43 2C   // $TMRTC,        // Header
   34 32 2C               // 42,            // Length
   30 2C 30 2C            // 0,0,           // transaction ID 0, mode 0
   30 37 2C               // 07,            // Error Code 07
   56 61 6C 75 65 45 72 72 6F 72 3B 54 68 65 20 76 61 6C 75 65 20 69 73 20 6E 6F 74 20 73
   75 70 70 6F 72 74      // ValueError;The value is not support        // Unsupported value error
   2C 2A 34 34 0D 0A      // ,*47\r\n       // Checksum
```

23. Compliance Functions

23.1 Compliance Class

Use the Compliance class and declare variables to provide users with the robot compliance control setting and the stop conditions.

Construct 1

Compliance *VariableName*

Parameters No input parameter

Note

Compliance cp1 // Declare compliance control variable.

Member Methods

Name	Default	Description
Reset()		Reset all the compliance control motion parameters to the default.
Frame()	1	Set the reference coordinate of the compliance control motion.
HighResistance()	false	Resistance on the non-motion direction (X,Y,Z).
Single()		The single axis parameter of the compliance control motion
Teach()		The teach parameter of the compliance control motion
Multiple()		The multiple axes parameter of the compliance control motion
Impedance		The impedance parameter of the compliance control motion
Timeout()	-	The stop condition of timeout
DInput()	-	The stop condition of digital input
AInput()	-	The stop condition of analog input
Condition()	-	The stop condition of the conditional expression
Start()	true	Start the compliance control motion.
Stop()		Stop the compliance control motion.

23.1.1 Reset()

Reset all the compliance control motion parameters to the default.

Syntax 1

void **Reset**(
)

Parameters

void No input value

Return

void No return

23.1.2 Frame()

Set the reference base of the compliance control motion.

Syntax 1

void **Frame**(
int
)

Parameters

int	The base associated with the control motion	
	1	Tool
	2	The current base

Return

void	No return

23.1.3 HighResistance()

Set the resistance on the non-motion direction (X,Y,Z).

Syntax 1

void **HighResistance**(
bool
)

Parameters

bool	The resistance on the non-motion direction (X,Y,Z)	
	false	Default
	true	High resistance

Return

void	No return

23.1.4 Single()

Set the single axis parameters of compliance control motion.

Syntax 1

void **Single**(
int or string,
int
)

Parameters

int or string	Direction						
	0	or "X"	X	3	or "RX"		RX
	1	or "Y"	Y	4	or "RY"		RY
	2	or "Z"	Z	5	or "RZ"		RZ
int	Distance X,Y,Z (mm) RX,RY,RZ (degree)						

Return

void	No return

23.1.5 Teach()

Set the teach parameters of compliance control motion.

Syntax 1

void **Teach**(
int or string,
float[] or string,
float[] or string,
int
)

Parameters

int or string
Linear direction or rotating direction
0 or "Linear" Linear direction
1 or "Rotation" Rotating direction

float[] or string
The 1st point $\{X_{1(mm)}\ Y_{1(mm)}\ Z_{1(mm)}\ RX_{1(°)}\ RY_{1(°)}\ RZ_{1(°)}\}$ or
The name of the 1st point (use the robot TCP coordinate)

float[] or string
The 2nd point $\{X_{2(mm)}\ Y_{2(mm)}\ Z_{2(mm)}\ RX_{2(°)}\ RY_{2(°)}\ RZ_{2(°)}\}$ 或
The name of the 2nd point (use the robot TCP coordinate

int Adjustment range Linear (mm) Rotation (degree)

Return

void No return

23.1.6 Multiple()

Set the Multiple Axes parameters of compliance control motion.

Syntax 1

void **Multiple**(
int or string,
bool,
int,
int,
)

Parameters

int or string
Direction

0	or	"X"	X	3	or	"RX"	RX
1	or	"Y"	Y	4	or	"RY"	RY
2	or	"Z"	Z	5	or	"RZ"	RZ

bool Enable the control to the assigned direction or not.
false Disable
true Enable

int Distance restriction upper bound X,Y,Z (mm) RX,RY,RZ (degree)

int Distance restriction lower bound X,Y,Z (mm) RX,RY,RZ (degree)

Return

void No return

Syntax 2

void **Multiple**(
int or string,
bool
)

Note

Same as Syntax 1 parameter definitions for setting whether to enable the control to the assigned direction.

23.1.7 Impedance()

Set the impedance parameters of compliance control motion.

Syntax 1

void **Impedance**(
int or string,
int
)

Parameters

int or string — Axes to release
0 or "All" Release all axes
1 or "XYZ" Release X, Y, Z
2 or "RXYZ" Release RX, RY, RZ

int — Rigidity level
0 Soft
1 Intermediate
2 Stiff

Return

void — No return

23.1.8 Timeout()

Set the stop condition of timeout.

Syntax 1

void **Timeout**(
int
)

Parameters

int — Timeout in milliseconds
< 0 Disable
>= 0 Timeout duration

Return

void — No return

Syntax 2

void **Timeout**(
)

Parameters

void	No parameterfor cancelling the stop condition.

Return

void	No return

23.1.9 DInput()

Set the stop condition of the digital input.

Syntax 1

void **DInput**(
string,
int,
int or string
)

Parameters

string	Control module name	
	ControlBox	The control box
	EndModule	The end module
	ExtModuleN	The external module (N = 0 .. n)
int	Input channel 0 .. n	
int or string		
	Set the stop condition to Low/High.	
	0 or "L"	Low
	1 or "H"	High

Return

void	No return

Syntax 2

void **DInput**(
int
)

Parameters

int	The stroke ratio to start receiving digital input (valid when the operation mode is " Compliance ")

Return

void	No return

Syntax 3

void **DInput**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

23.1.10 AInput()

Set the stop condition of the analog input.

Syntax 1

void **AInput**(
    string,
    int,
    int or string,
    float
)

Parameters

string	Control module name		
	ControlBox		The control box
	EndModule		The end module
	ExtModuleN		The external module (N = 0 .. n)
int	Input channel 0 .. n		
int or string			
	Set the condition to judge		
	0	or ">"	Greater than
	1	or ">="	Greater than or equal to
	2	or "=="	Equal to (Recommend not to use since it is not easy to hold the equal condition with analog input.)
	3	or "<="	Less than or equal to
	4	or "<"	Less than
float	Condition value		

Return

void	No return

Syntax 2

void **AInput**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

23.1.11 Condition()

Set the stop condition of the conditional expression.

Syntax 1

void **Condition**(
    bool or ?
)

Parameters

bool or ? The conditional that can be true/false or a bool return of the statement.

Return

void No return

Syntax 2

void **Condition**(

)

Parameters

void No parameter for cancelling the stop condition.

Return

void No return

23.1.12 Start()

Start the compliance control motion.

Syntax 1

int **Start**(

)

Parameters

void No input value

Return

int Return the result value after the force control motion stops.

0	Not Working
1	Working
2	Timeout
3	Distance reached
4	IO triggered
5	Resisted
6	Error
14	Over Speed
201	Digital IO triggered
202	Analog IO triggered
203	Variable
204	Force is comprehended
205	Allowable Position Tolerances
206	Motion Finish

23.1.13 Stop()

Stop the compliance control motion.

Syntax 1

int **Stop**(

)

Parameters

void No input value

Return

int Return the result value after the compliance control motion stops.

- **Parameter Settings**

```
Compliance cp1                    // Declare the compliance control variable.
(1)
    cp1.Frame(1)                  // Set the compliance control base as tool.
    cp1.Frame(2)                  // Set the compliance control base as the current base (will overwrite the
                                  previous setting).
    cp1.Reset()                   // Reset all parameters
(2)
    cp1.Frame(1)
    cp1.Single("X", 30)           // Set direction X with distance of 30mm
    cp1.Single("Z", 40)           // Set direction Z with distance of 40mm (will overwrite the previous Single
                                  setting)
    cp1.Reset()                   // Reset all parameters
(3)
    cp1.Frame(1)
    cp1.HighResistance(true) // Set the resistance on the non-motion direction to High Resistance
    // Control
    cp1.Single("Z", 40)           // Set direction Z with distance of 40mm (use Single mode)
    cp1.Teach("Linear", "P1", "P2", 0)          // Set the teach point P1 and P2 (will use Teach
                                                mode instead)
    cp1.AdvSet ("X", true, 100, -100)       // Set direction X with advanced parameters (will use
                                            Multiple mode instread)
    cp1.AdvSet ("Z", true, 100, -10030)     // Set direction Z
    cp1.AdvSet ("X", true, 10, -10)         // Set direction X with advanced parameters (will overwrite
                                            the previous Multiple X parameter)
    cp1.Impedance("All", 1)       // Set the impedance parameter (will use Impedance mode instead)
    // Stop Criteria
    cp1.Timeout(10000)                      // Set timeout to 10000ms
    cp1.DInput("ControlBox", 0, "H")        // When ControlBox DI0 is High
    cp1.AInput("ControlBox", 0, ">=", 3.3)  // When ControlBox AI0 is greater than or equal to 3.3V
    int count = 0
    cp1.Condition(count > 1000)   // conditional expression
    cp1.Reset()                   // Reset all parameters
```

- **Compliance Control**

```
Compliance cp1
(1) Single Axis
    PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
    cp1.Single("Z", 100)              // Set direction Z with distance of 100mm
    int re = cp1.Start()              // Start the compliance control motion
    //    Set direction Z with a moving distance of 100mm, so it will move toward direction Z. Once the moving
          distance is comprehended, it stops the control motion, exits the function, and returns the result
          values.

(2) Teach
    TPoint P1 = {516.655,-147.754,445.381,179.444,-0.324,89.912},{0,0,90,0,90,0}
```

```
TPoint P2 = {517.419,-147.175,345.184,179.533,-0.319,89.918},{0.057,1.805,103.178,-14.896,89.998,0.085}
TPoint P3 = {516.655,-147.740,445.388,-162.754,-0.281,89.819},{0.017,6.570,77.958,23.270,89.971,-0.043}
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
cp1.Teach("Linear", "P1", "P2", 0)          // Set the teach point P1 and P2 in the linear direction
cp1.Timeout(5000)                           // Set timeout to 5000ms
int re = cp1.Start()                        // Start the compliance control motion
//    Teach the two points in the linear direction. Once the moving distance and the teach linear direction are comprehended, it stops the control motion, exits the function, and return the result values. Since the timeout is set, if it does not comprehend the moving distance in time, it stops the control motion, exits the function, and returns the result values.
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
cp1.Teach("Rotation", "P1", "P3", 0)
// Set the teach point P1 and P3 in the rotating direction
re = cp1.Start()
//    Teach the two points in the rotating direction. Once the moving distance and the teach rotating direction are comprehended, it stops the control motion, exits the function, and return the result values. Since the timeout is set (without resetting the timeout of CP1), if it does not comprehend the moving distance in time, it stops the control motion, exits the function, and returns the result values.
```

(3) Multiple Axis

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
cp1.Multiple("X", true, 100, -100)  // Set direction X with multiple axis parameters
cp1.Multiple("Z", true, 100, -100)  // Set direction Z with multiple axis parameters
cp1.Multiple("X", true, 100, -100)  // Set direction X with multiple axis parameters (will overwrite the previous multiple axis parameters).
int re = cp1.Start()                // Start the compliance control motion
//    Set direction X and Z for compliance control. Once the moving distance is comprehended, it stop the control motion, exits the function, and returns the result values.
```

(4) Impedance

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
cp1.Impedance("all", 1)                 // Release all axes
cp1.DInput("ControlBox", 0, "H")        // When ControlBox DI0 is High
int re = cp1.Start()                    // Start the compliance control motion
//    Release all axes. The robot stays put in the current position and complies with external forces to lessen the torque on the joints. When the stop criterion, ControlBox DI0 is High, is comprehended, it stop the control motion, exits the function, and returns the result values.
```

24. TouchStop Functions

24.1 TouchStop class

Use the TouchStop class and declare variables to provide users with the robot touch stop setting and the stop conditions to fulfill the touch stop function.

Construct1

TouchStop *VariableName* = string

TouchStop *VariableName* = string, string

Parameters

string	Operation mode "Compliance" "Line" "Force"
string	Device name of the sensor (valid when the operation mode is "Force")

note

```
TouchStop ts1 = "Compliance"      // Declare a touchstop control variable with the function of compliance
TouchStop ts2 = "Line"            // Declare a touchstop control variable with the function of line
FTSensor fts3 = "TMFT300"         // Build a deivce named TMFT300.
TouchStop ts3 = "Force", "fts3"   // Declare a touchstop control variable with the function of force tethered with the sensor device fts3.
```

Member Methods

Name	Default	Description
Reset()		Reset all the compliance control motion parameters to the default except the operation mode and the sensor device.
Frame()	1	Set the reference coordinate of the touchstop control motion.
HighResistance()	false	Resistance on the non-motion direction (X,Y,Z). (Valid when the operation mode is “Compliance”).
BrakeDistance()	0	(Valid when the operation mode is “Line”).
RecordPosPoint()	-	Set the record touchstop coordinate value to the point name.
Single()		The single axis parameter of the compliance control motion
Teach()		The teach parameter of the compliance control motion
AdvSet()		The advance setting parameter of the compliance control motion. (Valid when the operation mode is “Compliance”).
Timeout()	-	The stop condition of timeout
DInput()	-	The stop condition of digital input
AInput()	-	The stop condition of analog input
Condition()	-	The stop condition of the conditional expression
Resisted()	-	Stop condition of the external resistance detection. (Valid when the operation mode is “Compliance”).
FTReached()	-	The stop condition of monitoring the values of force, torque, or resultant force acquired. (Valid when the operation mode is “Force”).

Name	Default	Description
Start()	true	Start the compliance control motion.
Stop()		Stop the compliance control motion.
GetStoppedPos()	{0,0,0,0,0,0}	Get the stopped position values after the robot touch-stopped.
GetTriggeredPos()	{0,0,0,0,0,0}	Get the triggered position values after the robot touch-stopped.
GetMovingDistance()	0	Get the moving distance of the touchstop motion.

24.1.1 Reset()

Reset all the touchstop control motion parameters to the default except the operation mode and the sensor device

Syntax 1

void **Reset**(
)

Parameters

void No input value

Return

void No return

24.1.2 Frame()

Set the reference base of the touchtop control motion.

Syntax 1

void **Frame**(
int
)

Parameters

int The base associated with the control motion
1 Tool
2 The current base

Return

void No return

24.1.3 HighResistance()

Set the resistance on the non-motion direction (X,Y,Z). (Valid Valid when the operation mode is “Compliance”.)

Syntax 1

void **HighResistance**(
bool
)

Parameters

bool The resistance on the non-motion direction (X,Y,Z)

false Default
true High resistance

Return

void No return

24.1.4 BrakeDistance()

Set the braking distance. (Valid Valid when the operation mode is “Line”.)

Syntax 1

void **BrakeDistance**(
int
)

Parameters

int Braking distance in mm

Return

void No return

24.1.5 RecordPosPoint()

Set the record touchstop coordinate value to the point name.
* If in Flow projects, it requires to create the associated point name in the point manager. (Use the TouchStop node to create.)
* If in Script projects, it requires to specify the associated point name in the define section. (Define the point as "D" or "JD".)

Syntax 1

void **RecordPosPoint**(
string,
bool
)

Parameters

string The point name. Denote record canceled if empty string.
bool Record the touchstop stop point or the trigger point
false The stop point
true The trigger point

Return

void No return

Syntax 2

void **RecordPosPoint**(
string
)

Note

Same as Syntax 1. Fill false to the parameter of the recording the touchstop stop point or the trigger point

Syntax 3

void **RecordPosPoint**(
)

Parameters

void	No input value. Use to cancel recording the touchstop stop point or the trigger point

Return

void	No return

24.1.6 Single()

Set the single axis parameters of touchstop control motion.

Syntax 1

void **Single**(
int or string,
int,
int,
int
)

Parameters

int or string

Direction							
0	or	"X"	X	3	or	"RX"	RX
1	or	"Y"	Y	4	or	"RY"	RY
2	or	"Z"	Z	5	or	"RZ"	RZ

int Distance X,Y,Z (mm) RX,RY,RZ (degree)

If operation mode is Compliance	If operation mode is Line or Force
int	Force X,Y,Z (N) RX,RY,RZ (mNm)	Speed X,Y,Z (mm/s) RX,RY,RZ (degree/s)

int Target speed X,Y,Z (mm/s) RX,RY,RZ (degree/s) Accelerate time in millisecond

Return

void	No return

Syntax 2

void **Single**(
int or string,
int,
int,
int,
bool,
bool
)

Parameters

int or string

Direction							
0	or	"X"	X	3	or	"RX"	RX
1	or	"Y"	Y	4	or	"RY"	RY

2 or "Z" Z 5 or "RZ" RZ

int Distance X,Y,Z (mm) RX,RY,RZ (degree)

int Speed X,Y,Z (mm/s) RX,RY,RZ (degree/s)

int Accelerate time in millisecond

bool Cancel precision positioning

true Cancel precision positioning

false Precision positioning (default)

bool Synchronize to the project speed or not

true Synchronize to the project speed (default)

false Synchronize to the project speed not

Return

void No return

24.1.7 Teach()

Set the teach parameters of compliance control motion.

Syntax 1

```
void Teach(
    int or string,
    float[] or string,
    float[] or string,
    int,
    int,
    int
)
```

Parameters

int or string

Linear direction or rotating direction

0 or "Linear" Linear direction

1 or "Rotation" Rotating direction

float[] or string

The 1st point $\{X_{1(mm)} \quad Y_{1(mm)} \quad Z_{1(mm)} \quad RX_{1(°)} \quad RY_{1(°)} \quad RZ_{1(°)}\}$ or

The name of the 1st point (use the robot TCP coordinate)

float[] or string

The 2nd point $\{X_{2(mm)} \quad Y_{2(mm)} \quad Z_{2(mm)} \quad RX_{2(°)} \quad RY_{2(°)} \quad RZ_{2(°)}\}$ 或

The name of the 2nd point (use the robot TCP coordinate

int Adjustment range Linear (mm) Rotation (degree)

If operation mode is Compliance If operation mode is Line or Force

int Force X,Y,Z (N) RX,RY,RZ (mNm) Speed X,Y,Z (mm/s) RX,RY,RZ (degree/s)

int Target speed X,Y,Z (mm/s) RX,RY,RZ (degree/s) Accelerate time in millisecond

Return

void No return

Syntax 2

```
void Teach(
```

int or string,
float[] or string,
float[] or string,
int,
int,
int,
bool,
bool
)

Parameters

int or string
Linear direction or rotating direction
0 or "Linear" Linear direction
1 or "Rotation" Rotating direction

float[] or string
The 1st point $\{X_{1(mm)} \quad Y_{1(mm)} \quad Z_{1(mm)} \quad RX_{1(°)} \quad RY_{1(°)} \quad RZ_{1(°)}\}$ or
The name of the 1st point (use the robot TCP coordinate)

float[] or string
The 2nd point $\{X_{2(mm)} \quad Y_{2(mm)} \quad Z_{2(mm)} \quad RX_{2(°)} \quad RY_{2(°)} \quad RZ_{2(°)}\}$ 或
The name of the 2nd point (use the robot TCP coordinate

int Adjustment range Linear (mm) Rotation (degree)
int Speed X,Y,Z (mm/s) RX,RY,RZ (degree/s)
int Accelerate time in millisecond
bool Cancel precision positioning
true Cancel precision positioning
false Precision positioning (default)
bool Synchronize to the project speed or not
true Synchronize to the project speed (default)
false Synchronize to the project speed not

Return

void No return

24.1.8 AdvSet()

Set the advanced parameters of touchstop control motion. (Valid when the operation mode is “Compliance”.)

Syntax 1

void **AdvSet**(
int or string,
bool,
int,
int,
int,
int
)

Parameters

int or string

Direction

0	or	"X"	X	3	or	"RX"	RX
1	or	"Y"	Y	4	or	"RY"	RY
2	or	"Z"	Z	5	or	"RZ"	RZ

bool Enable the control to the assigned direction or not.
- false Disable
- true Enable

int Distance restriction upper bound X,Y,Z (mm) RX,RY,RZ (degree)

int Distance restriction lower bound X,Y,Z (mm) RX,RY,RZ (degree)

int Force X,Y,Z (N) RX,RY,RZ (mNm)

int Target speed X,Y,Z (mm/s) RX,RY,RZ (degree/s)

Return

void No return

Syntax 2

```
void AdvSet(
    int or string,
    bool
)
```

note

Same as Syntax 1 parameter definitions for setting whether to enable the control to the assigned direction.

24.1.9 Timeout()

Set the stop condition of timeout.

Syntax 1

```
void Timeout(
    int
)
```

Parameters

int Timeout in milliseconds
- < 0 Disable
- >= 0 Timeout duration

Return

void No return

Syntax 2

```
void Timeout(
)
```

Parameters

void No parameter for cancelling the stop condition.

Return

void No return

24.1.10 DInput()

Set the stop condition of the digital input.

Syntax 1

void **DInput**(
string,
int,
int or string
)

Parameters

string	Control module name	
	ControlBox	The control box
	EndModule	The end module
	ExtModuleN	The external module (N = 0 .. n)
int	Input channel 0 .. n	
int or string		
	Set the stop condition to Low/High.	
	0 or "L"	Low
	1 or "H"	High

Return

void	No return

Syntax 2

void **DInput**(
int
)

Parameters

Int	The stroke ratio to start receiving digital input (valid when the operation mode is " Compliance ")

Return

void	No return

Syntax 3

void **DInput**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

24.1.11 AInput()

Set the stop condition of the analog input.

Syntax 1

void **AInput**(
string,
int,
int or string,

float
)
Parameters

string	Control module name	
	ControlBox	The control box
	EndModule	The end module
	ExtModuleN	The external module (N = 0 .. n)
int	Input channel 0 .. n	
int or string		
	Set the condition to judge	
	0 or ">"	Greater than
	1 or ">="	Greater than or equal to
	2 or "=="	Equal to (Recommend not to use since it is not easy to hold the equal condition with analog input.)
	3 or "<="	Less than or equal to
	4 or "<"	Less than
float	Condition value	

Return

void	No return

Syntax 2

void **AInput**(
)
Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

24.1.12 Condition()

Set the stop condition of the conditional expression.

Syntax 1

void **Condition**(
bool or ?
)
Parameters

bool or ?	The conditional that can be true/false or a bool return of the statement.

Return

void	No return

Syntax 2

void **Condition**(
)
Parameters

void	No parameter for cancelling the stop condition.

Return

void No return

24.1.13 Resisted()

Set the stop condition of the external resistance detection. (valid when the operation mode is " Compliance ")

Syntax 1

void **Resisted**(
bool
)

Parameters

bool External resistance detection
false Disable
true Enable

Return

void No return

Syntax 2

void **Resisted**(
)

Parameters

void No parameter for cancelling the stop condition.

Return

void No return

24.1.14 FTReached()

Set the stop condition of monitoring the values of force, torque, or resultant force acquired. (valid when the operation mode is " Force")

Syntax 1

void **FTReached**(
int or string,
bool,
float
)

Parameters

int The values of force, torque, or resultant force.
6 or "F3D" F3D (N)
7 or "T3D" T3D (Nm)
8 or "Force" Force (N) (default)

Whether to enable monitoring the assigned the values of force, torque, or resultant force.
false Disable
true Enable

float The monitoring value

Return

void No return

Syntax 2

void **FTReached**(
int or string,
bool
)

Note

Same as syntax 1. Use to whether to enable monitoring the assigned the values of force, torque, or resultant force.

Syntax 3

void **FTReached**(
bool
)

Parameters

bool Whether to enable the absolute values monitoring.
false Disable
true Enable

Syntax 4

void **FTReached**(
)

Parameters

void No parameter for cancelling the stop condition.

Return

void No return

24.1.15 Start()

Start the touchstop control motion.

Syntax 1

int **Start**(
bool
)

Parameters

bool Zero out force sensor before execution. (valid when the operation mode is "Force")
true Enable (default)
false Disable

Return

int Return the result value after the touchstop control motion stops.
0 Not Working
1 Working
2 Timeout
3 Distance reached

4	IO triggered
5	Resisted
6	Error
14	Over Speed
201	Digital IO triggered
202	Analog IO triggered
203	Variable
204	Force is Comprehended
205	Allowable Position Tolerances
206	Motion Finish

Syntax 2

int **Start**(
)

note

Same as syntax 1. Fill true to zero out force sensor before execution.

24.1.16 Stop()

Stop the touchstop control motion.

Syntax 1

int **Stop**(
)

Parameters

void No input value

Return

int Return the result value after the touchstop control motion stops.

24.1.17 GetStoppedPos()

Get the stopped position values after the robot touch-stopped.

Syntax 1

void **GetStoppedPos**(
int
)

Parameters

int Get the coordinate value or the angle value of the stop point of the touch-stop control motion.

0	the robot flange center coordinate (by the current base)
1	the robot joint angle
2	the robot end TCP coordinate (by the current base)
3	the robot TCP coordinate (by the RobotBase base)
4	the robot end TCP coordinate (by the RobotBase base)

Return

float[]	If in coordinates, it is the six elements of the robot coordinates: X(mm), Y(mm), Z(mm), RX(°), RY(°), and RZ(°); if in angle, the six elements of the robot joint: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), and Joint 6(°)

24.1.18 GetTriggeredPos()

Get the triggered position values after the robot touch-stopped.

Syntax 1

void **GetTriggeredPos**(
    int
)

Parameters

int	Get the coordinate value or the angle value of the stop point of the touch-stop control motion.
0	the robot flange center coordinate (by the current base)
1	the robot joint angle
2	the robot end TCP coordinate (by the current base)
3	the robot TCP coordinate (by the RobotBase base)
4	the robot end TCP coordinate (by the RobotBase base)

Return

float[]	If in coordinates, it is the six elements of the robot coordinates: X(mm), Y(mm), Z(mm), RX(°), RY(°), and RZ(°); if in angle, the six elements of the robot joint: Joint 1(°), Joint 2(°), Joint 3(°), Joint 4(°), Joint 5(°), and Joint 6(°)

24.1.19 GetMovingDistance()

Get the moving distance of the touchstop motion.

Syntax 1

float **GetMovingDistance**(
)

Parameters

void	No input value

Return

float	Return the moving distance of the touchstop motion in mm.

- **Parameter Settings**

```
TouchStop ts1 = "Compliance"      // Declare the touchstop control variable functioning as Compliance.
TouchStop ts2 = "Line"            // Declare the touchstop control variable functioning as Line.
FTSensor fts3 = "TMFT300"         // Construct the device TMFT300.
TouchStop ts3 = "Force", "fts3"   // Declare the touchstop control variable and tether fts3 as the
                                  sensor name.
TPoint P0 = "JD",{0,0,0,0,0,0}
```

(1)

```
ts1.Frame(1)                    // Set the touchstop control base as tool.
ts1.Frame(2)                    // Set the touchstop control base as the current base (will overwrite the previous setting).
ts1.Reset()                     // Reset all parameters
```

(2)

```
ts1.Frame(1)
ts1.Single("X", 30, 30, 30)     // Set direction X with distance of 30mm, force of 30N, and target speed of 30 mm/s
ts1.Single("Z", 40, 30, 30)     // Set direction Z with distance of 40mm (will overwrite the previous Single setting)
ts1.Reset()                     // Reset all parameters
ts2.Single("Z", 30, 40, 500, false, true)   // Set direction Z with distance of 30mm, target of 40mm/s, and accelerate time of 500ms.
```

(3)

```
ts1.Frame(1)
ts1.HighResistance(true)        // Set the resistance on the non-motion direction to High Resistance
ts2.BrakeDistance(20)           // Set the braking distance to 20mm
ts2.RecordPosPoint("P0", true)  // Set the record touchstop coordinate value to P0.

// Control
ts1.Single("Z", 40, 30, 30)                     // Set direction Z with distance of 40mm (use Single mode)
ts1.Teach("Linear", "P1", "P2", 0, 30, 30)      // Set the teach point P1 and P2 (will use Teach mode instead)
ts1.AdvSet ("X", true, 100, -100, 30, 30)       // Set direction X with advanced parameters (will use Advanced mode instread)
ts1.AdvSet ("Z", true, 100, -100, 30, 30)       // Set direction Z with advanced parameters
ts1.AdvSet ("X", true, 10, -10, 30, 30)         // Set direction X with advanced parameters (will overwrite the previous AdvSet X parameter)

// Stop Criteria
ts1.Timeout(10000)                              // Set timeout to 10000ms
ts1.DInput("ControlBox", 0, "H")                // When ControlBox DI0 is High
ts1.DInput(100)                                 // Start receiving digital input with stroke ratio to 100%
ts1.AInput("ControlBox", 0, ">=", 3.3)          // When ControlBox AI0 is greater than or equal to 3.3V
int count = 0
ts1.Condition(count > 1000)                     // conditional expression
ts1.Resisted(true)                              // external resistance detection
ts1.Reset()                     // Reset all parameters (reserve tethering "fts1" as sensor name)
ts3.FTReached("Force", true, 10)    // Enable monitoring of the resultant force of the control direction to satisfy 10N.
ts3.FTReached(true)             // Enable monitoring of the absolute values
```

• Touchstop Compliance

```
TouchStop ts1 = "Compliance"    // Declare the touchstop control variable functioning as Compliance.
TPoint P0 = "JD",{0,0,0,0,0,0}
```

(1) Single Axis

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts1.Single("Z", 100, 30, 30)                    // Set timeout to 10000ms
ts1.AInput("ControlBox", 0, ">=", 3.3)          // When ControlBox AI0 is greater than or equal to 3.3V
ts1.RecordPosPoint("P0", false)                 // Set the record touchstop coordinate value to P0.
int re = ts1.Start()                            // Start the touchstop compliance control motion
//    Set direction Z with a moving distance of 100mm, a force of 30N, and a target speed of 30 mm/s, so it
      will move toward direction Z. When the stop criterion, ControlBox AI0 is greater than or equal to 3.3V,
      is comprehended, it stops the control motion, exits the function, and returns the result values.
```

(2) Teach

```
TPoint P1 = {516.655,-147.754,445.381,179.444,-0.324,89.912},{0,0,90,0,90,0}
TPoint P2 = {517.419,-147.175,345.184,179.533,-0.319,89.918},{0.057,1.805,103.178,-
14.896,89.998,0.085}
TPoint P3 = {516.655,-147.740,445.388,-162.754,-0.281,89.819},{0.017,6.570,77.958,23.270,89.971,-
0.043}
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts1.Teach("Linear", "P1", "P2", 0, 40, 40)// Set the teach point P1 and P2 in the linear direction
ts1.Timeout(5000)                               // Set timeout to 5000ms
int re = ts1.Start()                            // Start the touchstop compliance control motion
//    Teach the two points in the linear direction with a force of 40N and a target speed of 40 mm/s. Once
      the moving distance and the teach linear direction are comprehended, it stops the control motion,
      exits the function, and return the result values. Since the timeout is set, if it does not comprehend the
      moving distance in time, it stops the control motion, exits the function, and returns the result values.
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts1.Teach("Rotation", "P1", "P3", 0, 5000, 40)
// Set the teach point P1 and P3 in the rotating direction
re = ts1.Start()
//    Teach the two points in the rotating direction with a force of 5000mNm and a target speed of 40
      mm/s. Once the moving distance and the teach rotating direction are comprehended, it stops the
      control motion, exits the function, and return the result values. Since the timeout is set (without
      resetting the timeout of ts1), if it does not comprehend the moving distance in time, it stops the control
      motion, exits the function, and returns the result values.
```

(3) Advanced

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts1.AdvSet("X", true, 100, -100, 30, 30)  // Set direction X with advanced parameters
ts1.AdvSet("Z", true, 100, -100, 30, 30)  // Set direction Z with advanced parameters
ts1.AdvSet("X", true, 100, -100, 40, 40)  // Set direction X with advanced parameters (will overwrite
                                             the previous AdvSet X parameter)
int re = ts1.Start()                            // Start the touchstop compliance control motion
//    Set direction X and Z for compliance control. Once the moving distance is comprehended, it stops the
      control motion, exits the function, and returns the result values.
```

● Touchstop Line

```
TouchStop ts2 = "Line"          // Declare the touchstop control variable functioning as Line
TPoint P0 = "JD",{0,0,0,0,0,0}
```

(1) Single Axis

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
```

```
ts2.Single("Z", 100, 30, 500)              // Set direction Z with distance of 100mm
ts2.DInput("ControlBox", 0, "H")           // When ControlBox DI0 is High
ts2.RecordPosPoint("P0", true)             // Set the record touchstop coordinate value to P0.
int re = ts2.Start()                       // Start the touchstop control motion
//    Set direction Z for control with a moving distance of 100mm, an accelerate time of 500ms, and a
      target speed of 30 mm/s, so it will move toward direction Z. Once the moving distance is
      comprehended, it stops the control motion, exits the function, and return the result values. When the
      stop criterion, ControlBox DI0 is High, is comprehended, it stops the control motion, exits the function,
      and returns the result values.
```

(2) Teach

```
TPoint P1 = {516.655,-147.754,445.381,179.444,-0.324,89.912},{0,0,90,0,90,0}
TPoint P2 = {517.419,-147.175,345.184,179.533,-0.319,89.918},{0.057,1.805,103.178,-
14.896,89.998,0.085}
TPoint P3 = {516.655,-147.740,445.388,-162.754,-0.281,89.819},{0.017,6.570,77.958,23.270,89.971,-
0.043}
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts2.Teach("Linear", "P1", "P2", 0, 40, 500)   // Set the teach point P1 and P2 in the linear
                                                 direction
ts2.Timeout(5000)                          // Set timeout to 5000ms
int re = ts2.Start()                       // Start the touchstop control motion
//    Teach the two points in the linear direction with an accelerate time of 500ms and a target speed of 40
      mm/s. Once the moving distance and the teach linear direction are comprehended, it stops the
      control motion, exits the function, and return the result values. Since the timeout is set, if it does not
      comprehend the moving distance in time, it stops the control motion, exits the function, and returns
      the result values.

PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts2.Teach("Rotation", "P1", "P3", 0, 40, 500) // Set the teach point P1 and P3 in the rotating
                                                 direction
re = ts2.Start()
//    Teach the two points in the rotating direction with an accelerate time of 500ms and a target speed of
      40 mm/s. Once the moving distance and the teach rotating direction are comprehended, it stops the
      control motion, exits the function, and return the result values. Since the timeout is set (without
      resetting the timeout of ts1), if it does not comprehend the moving distance in time, it stops the control
      motion, exits the function, and returns the result values.
```

● Touchstop Force

```
FTSensor fts3 = "TMFT300"          // Construct the device TMFT300.
TouchStop ts3 = "Force", "fts3"    // Declare the touchstop control variable and tether fts3 as the
                                      sensor name.
TPoint P0 = "JD",{0,0,0,0,0,0}
```

(1) Single Axis

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts3.Single("Z", 100, 30, 500)              // Set direction Z with distance of 100mm
ts3.DInput("ControlBox", 0, "H")           // When ControlBox DI0 is High
ts3.FTReached("Force", true, 2)            // Enable monitoring of the resultant force of the control
```

direction to satisfy 2N.

```
ts3.RecordPosPoint("P0", true)      // Set the record touchstop coordinate value to P0.
int re = ts3.Start()                // Start the touchstop control motion
//      Set direction Z for control with a moving distance of 100mm, an accelerate time of 500ms, and a
        target speed of 30 mm/s, so it will move toward direction Z. Once the moving distance is
        comprehended, it stops the control motion, exits the function, and returns the result values. When the
        stop criterion, ControlBox DI0 is High, is comprehended, it stop the control motion, exits the function,
        and returns the result values. Since the stop criterion on the monitoring of the resultant force is set, if
        it does not comprehend the moving distance in time, it stops the control motion, exits the function,
        and returns the result values.
```

(2) Teach

```
TPoint P1 = {516.655,-147.754,445.381,179.444,-0.324,89.912},{0,0,90,0,90,0}
TPoint P2 = {517.419,-147.175,345.184,179.533,-0.319,89.918},{0.057,1.805,103.178,-
14.896,89.998,0.085}
TPoint P3 = {516.655,-147.740,445.388,-162.754,-0.281,89.819},{0.017,6.570,77.958,23.270,89.971,-
0.043}
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts3.Teach("Linear", "P1", "P2", 0, 40, 500)     // Set the teach point P1 and P2 in the linear
                                                   direction
ts3.Timeout(5000)                   // Set timeout to 5000ms
ts3.FTReached("F3D", true, 2)       // Enable monitoring of the force of the control direction to
                                       satisfy 2N.
int re = ts3.Start()                // Start the touchstop control motion
//      Teach the two points in the linear direction with an accelerate time of 500ms and a target speed of 40
        mm/s. Once the moving distance and the teach linear direction are comprehended, it stops the
        control motion, exits the function, and return the result values. Since timeout is set, if it does not
        comprehend the moving distance in time, it stops the control motion, exits the function, and returns
        the result values. Since the stop criterion on the monitoring of the resultant force is set, if it does not
        comprehend the moving distance in time, it stops the control motion, exits the function, and returns
        the result values.
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
ts3.Timeout()                       // Cancel the timout stop criterion.
ts3.Teach("Rotation", "P1", "P3", 0, 40, 500)
// Set the teach point P1 and P3 in the rotating direction
re = ts3.Start()
//      Teach the two points in the rotating direction with an accelerate time of 500ms and a target speed of
        40 mm/s. Once the moving distance and the teach rotating direction are comprehended, it stops the
        control motion, exits the function, and return the result values. Since the stop criterion on the
        monitoring of the resultant force is set (without resetting the stop criterion on the resultant force of
        ts3), if it does not comprehend the moving distance in time, it stops the control motion, exits the
        function, and returns the result values.
```

25. Force Control Functions

25.1 FTSensor Class

Use FTSensor class and declare variables to create a Force Torque Sensor device. The variable name will be the device name.

Construct 1

FTSensor *VariableName* = string, string, float[], float[], float
FTSensor *VariableName* = string, float[], float[], float
FTSensor *VariableName* = string, string
FTSensor *VariableName* = string

Parameters

string	Supported models from the sensor suppliers "TMFT300" "OnRobot_HEX-E" "OnRobot_HEX-H" "ROBOTIQ_FT300" "SCHUNK_Axia80" "SRI_M4313N3C" " WACOH_WEF_WKF_115200" "WEF-6A200-4-RG24_9600"
string	connection description required when using serial port for communication
float[]	Position setting: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)
float[]	TCP value: X(mm), Y(mm), Z(mm)
float	Tool Mass: kg

Note

```
FTSensor fts_1 = "TMFT300","COM2"   // Construct the device TMFT300. The connection parameters are void for using EtherCAT communication.
FTSensor fts_2 = "TMFT300"          // Construct the device TMFT300
FTSensor fts_3 = "ROBOTIQ_FT300","COM2"
// Construct the device ROBOTIQ_FT300. Require to assign the connection port for using serial port communication.
FTSensor fts_4 = "ROBOTIQ_FT300","COM2",{0,0,0,0,0,0},{0.12,0.24,0.36},1
// Construct the device ROBOTIQ_FT300. Require to assign the connection port for using serial port communication and to configure the settings of the sensor position and tool mass center.
```

* If not filling position setting, TCP value, or tool mass, it uses the parameters in the force sensor setting in the project.
* After construction, either in flow projects or script projects, the device will not connect actively until proceeding to read or write.

Member Attributes

Name	Type	Mode	Description	Format
X	float	R	The strength value of the X axis	
Y	float	R	The strength value of the y axis	
Z	float	R	The strength value of the z axis	
TX	float	R	The torque value of the X axis	

Name	Type	Mode	Description	Format
TY	float	R	The torque value of the y axis	
TZ	float	R	The torque value of the z axis	
F3D	float	R	The XYZ force strength value	
T3D	float	R	The XYZ torque value	
Value	float[]	R	The XYZ force strength value and torque value array.	{X, Y, Z, TX, TY, TZ}, Size = 6
ForceValue	float[]	R	The XYZ force strength value array	{X, Y, Z}, Size = 3
TorqueValue	float[]	R	The XYZ torque value array	{TX, TY, TZ}, Size = 3
RefCoordX	float	R	The X-axis strength value measured based on the reference base set in the node	
RefCoordY	float	R	The Y-axis strength value measured based on the reference base set in the node	
RefCoordZ	float	R	The Z-axis strength value measured based on the reference base set in the node	
RefCoordTX	float	R	The X-axis torque value measured based on the reference base set in the node	
RefCoordTY	float	R	The Y-axis torque value measured based on the reference base set in the node	
RefCoordTZ	float	R	The Z-axis torque value measured based on the reference base set in the node	
RefCoordF3D	float	R	The XYZ strength measured based on the reference base set in the node	
RefCoordT3D	float	R	The XYZ torque measured based on the reference base set in the node	
RefCoordForceValue	float[]	R	The XYZ strength value matrix measured based on the reference base set in the node	{RefCoordX, RefCoordY, RefCoordZ}, Size = 3
RefCoordTorqueValue	float[]	R	The XYZ torque value matrix measured based on the reference base set in the node	{RefCoordTX, RefCoordTY, RefCoordTZ}, Size = 3
Model	string	R	The Model name of the F/T sensor	
Zero	byte	R/W	Turn on or off F/T sensor offset	0: Zero OFF, 1: Zero ON

Attributes associated with RefCoord come with values when in Force Control motions.

Member Methods

Name	Description
Open()	Connect to the sensor device.

Close()	Disconnect from the sensor device.

25.1.1 Open()

Open the connection to the Force Torque Sensor.

Syntax 1

bool **Open**(
)

Parameters

void	No parameter	

Return

bool	True	open successfully
	False	open unsuccessfully (the project returns an error)

* After opening the device, it proceeds to the connection to communicate. It may take a while to get the values due to different sensor models.

25.1.2 Close()

Close the connection from the Force Torque Sensor.

Syntax 1

bool **Close**(
)

Parameters

void	No parameter	

Return

bool	True	close successfully
	False	close unsuccessfully

Note

```
FTSensor fts_1 = "ROBOTIQ_FT300","COM2"
fts_1.Open() // Connect to the device.
fts_1.Close()// Disconnect from the device.
```

25.2 Force Class

Use Force class and declare variables for users to set the robot target force and torque parameters to reach a variety of associated force control motions.

Construct 1

Force *VariableName* = string

Parameters

string	sensor name

Note

```
FTSensor fts1 = "TMFT300"     // Construct the device TMFT300.
Force fc1 = "fts1"        // Declare the force control variable and tether fts1 as the sensor name.
```

Member Methods

Name	Defaults	Description
Reset()		Reset all the force control motion parameters to the default except the sensor name.
Frame()	1	Set the reference coordinate of the force control motion.
Distance()	-	The moving distance of the force control motion (Available only in the SetPoint F/T operation mode.)
ProtectionSpeed()		The speed protection of the force control motion
FTSet()	0,false,5,2,-1 1,false,5,2,-1 2,false,5,2,-1 3,false,0.5,2,-1 4,false,0.5,2,-1 5,false,0.5,2,-1	The force and the torque of the force control motion. The positive and negative values denote the force control direction. Users can adjust the PID control parameters.
Trajectory()	-	The trajectory path of the force control motion. (Trajectory F/T operation mode.)
Timeout()	-	Stop condition of timeout (Available only in the single F/T operation mode.)
AllowPosTol()	-	Stop condition of tolerant position error
DInput()	-	Stop condition of digital input
AInput()	-	Stop condition of analog input
FTReached()	-	The stop condition of monitoring the values of force, torque, or resultant force acquired.
Condition()	-	Stop condition of the conditional expression
Start()	true,false	Start the force control motion.
Stop()		Stop the force control motion.

25.2.1 Reset()

Reset all the force control motion parameters to the default except the sensor name.

Syntax 1

void **Reset**(
)

Parameters

void No parameter

Return

void No return

25.2.2 Frame()

Set the reference base of the force control motion.

Syntax 1

void **Frame**(
int
)

Parameters

int — The base associated with the control motion
- 0 The robot base
- 1 Tool: the base is coupled with the orientation of the tool coordinate. (default)
- 2 The current base
- 3 Trajectory: the base changes with the path.

Return

void — No return

Syntax 2

void **Frame**(
string
)

Parameters

string — Point name. Use the TCP coordinate of the point as the base associate with the control motion.

Return

void — No return

Syntax 3

void **Frame**(
float[],
string
)

Parameters

float[] — The TCP coordinate of the robot end point: X(mm), Y(mm), Z(mm), RX(°), RY(°), RZ(°)

string — Base name. Use the current base name if empty string.

Return

void — No return

Syntax 4

void **Frame**(
float[]
)

Note

Same as syntax 3. Fill RobotBase in Base name.

Syntax 5

void **Frame**(
float, float, float, float, float, float,
string
)

Note

Same as syntax 3. Replace the type float[] with the parameters in float .

Syntax 6

void **Frame**(
float, float, float, float, float, float

)

Note

Same as syntax 4. Replace the type float[] with the parameters in float .

25.2.3 Distance()

Set the moving distance of the force control motion. (Available only in the SetPoint F/T operation mode.)

Syntax 1

void **Distance**(
int
)

Parameters

int	Distance mm	
	< 0	No limit to the moving distance.
	>= 0	Limited to the moving distance. (Distance calculated from the starting point where the force control motion begins.)

Return

void No return

25.2.4 ProtectionSpeed()

Set the speed protection of the force control motion.

Syntax 1

void **ProtectionSpeed**(
int, int, int, int, int, int
)

Parameters

int, int, int, int, int, int

Set the speed protection against the axial force or torque: X(mm/s), Y(mm/s), Z(mm/s), RX(deg/s), RY(deg/s), RZ(deg/s)

<= 0	No limit to the speed.
> 0	Limited to the speed

* FTSet() is required to enable speed protection against the respective axial force or torque.
* Speed protection is available to configure in FTSet() as well.

Return

void No return

25.2.5 FTSet()

Set the force and the torque of the force control motion. The positive and negative values denote the force control direction. Users can adjust the PID control parameters.

Syntax 1

void **FTSet**(
int or string,

bool,
float,
int
int
)

Parameters

int or string — Axis force or axis torque

0	or	"FX"	FX (N)	3	or	"TX"	TX (Nm)
1	or	"FY"	FY (N)	4	or	"TY"	TY (Nm)
2	or	"FZ"	FZ (N)	5	or	"TZ"	TZ (Nm)

bool — Whether to enable the control of the assigned axis force or axis torque

false	Disable
true	Enable

float — The control value of force or torque. The positive and negative values denote the force control direction.

int — PID control parameter

(weak)				(strong)
0	1	2	3	4

int — Speed protection

<= 0	No limit to the speed.
> 0	Limited to the speed

Return

void — No return

Syntax 2

void **FTSet**(
int or string,
bool,
float,
int
)

Note

Same as syntax 1. Fill -1 to Speed protection parameter for no speed limit.

Syntax 3

void **FTSet**(
int or string,
bool,
float
)

Note

Same as syntax 1 parameter definition. Fill 2 to PID control parameter and -1 to Speed protection parameter for no speed limit.

Syntax 4

void **FTSet**(

int or string,
bool
)

Note

Same as syntax 1 parameter definition. Use to set whether to enable the control of the assigned axis force or axis torque only. No change to other parameters (Axis force or axis torque control value, PID control parameter, and Speed protection parameter).

Syntax 5

void **FTSet**(
int or string,
float
)

Note

Same as syntax 1 parameter definition. Use to set the control value of force or torque. No change to other parameters (Whether to enable to the control, PID control parameter, and Speed protection parameter).

Syntax 6

void **FTSet**(
int or string,
float,
int
)

Note

Same as syntax 1 parameter definition. Use to set Axis force or axis torque control value and speed control. only. No change to other parameters (Whether to enable to the control and PID control parameter).

Syntax 7

void **FTSet**(
int or string,
float[]
)

Parameters

int or string — Axis force or axis torque

0	or	"FX"	FX (N)	3	or	"TX"	TX (Nm)
1	or	"FY"	FY (N)	4	or	"TY"	TY (Nm)
2	or	"FZ"	FZ (N)	5	or	"TZ"	TZ (Nm)

float[] — PID control parameter {Kp, Ki, Kd}

Note

Same as syntax 1 parameter definition. Use to set PID control parameter (Kp, Ki, Kd) only. No change to other parameters (Whether to enable to the control, Axis force or axis torque control value, and speed control).

25.2.6 Trajectory()

.

Set the trajectory path of the force control motion. (Trajectory F/T operation mode.)

Syntax 1

void **Trajectory**(
    string
)

Parameters

string	Subflow name. Use in flow projects only. Return errors if use in script projects.

Return

void	No return

Syntax 2

void **Trajectory**(
    ?
)

Parameters

?	Trajectory path. Be a statement or a customized function

Return

void	No return

Syntax 3

void **Trajectory**(
)

Parameters

void	No parameter for cancelling trajectory F/T operation mode. (Change to the SetPoint F/T operation mode.)

Return

void	No return

25.2.7 Timeout()

Set the stop condition of timeout. (Available only in the SetPoint F/T operation mode.)

Syntax 1

void **Timeout**(
    int
)

Parameters

int	Timeout in milliseconds	
	< 0	Disable
	>= 0	Timeout duration

Return

void	No return

Syntax 2

void **Timeout**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

25.2.8 AllowPosTol()

Set the stop condition of the tolerant position error.

Syntax 1

```
void AllowPosTol(
    int
)
```

Parameters

int	Error distance in mm	
	< 0	Disable
	>= 0	Distance of the tolerant error.

Return

void	No return

Syntax 2

```
void AllowPosTol(
)
```

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

25.2.9 DInput()

Set the stop condition of the digital input.

Syntax 1

```
void DInput(
    string,
    int,
    int or string
)
```

Parameters

string	Control module name	
	ControlBox	The control box
	EndModule	The end module
	ExtModuleN	The external module (N = 0 .. n)
int	Input channel 0 .. n	
int or string		
	Set the stop condition to Low/High.	
	0 or "L"	Low
	1 or "H"	High

Return

void	No return

Syntax 2

void **DInput**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

25.2.10 AInput()

Set the stop condition of the analog input.

Syntax 1

void **AInput**(
string,
int,
int or string,
float
)

Parameters

string	Control module name		
	ControlBox		The control box
	EndModule		The end module
	ExtModuleN		The external module (N = 0 .. n)
int	Input channel 0 .. n		
int or string			
	Set the condition to judge		
	0	or ">"	Greater than
	1	or ">="	Greater than or equal to
	2	or "=="	Equal to (Recommend not to use since it is not easy to hold the equal condition with analog input.)
	3	or "<="	Less than or equal to
	4	or "<"	Less than
float	Condition value		

Return

void	No return

Syntax 2

void **AInput**(
)

Parameters

void	No parameter for cancelling the stop condition.

Return

void	No return

25.2.11 FTReached()

Set the stop condition of monitoring the values of force, torque, or resultant force acquired.

Syntax 1

void **FTReached**(
int or string,
bool,
float
)

Parameters

int — The values of force, torque, or resultant force.

0	or	"FX"	FX (N)	3	or	"TX"	TX (Nm)
1	or	"FY"	FY (N)	4	or	"TY"	TY (Nm)
2	or	"FZ"	FZ (N)	5	or	"TZ"	TZ (Nm)
6	or	"F3D"	F3D (N)	7	or	"T3D"	T3D (Nm)

bool — Whether to enable monitoring the assigned the values of force, torque, or resultant force.

- false — Disable
- true — Enable

float — The monitoring value

Return

void — No return

Syntax 2

void **FTReached**(
int or string,
bool
)

Note

Same as syntax 1. Use to whether to enable monitoring the assigned the values of force, torque, or resultant force.

Syntax 3

void **FTReached**(
bool
)

Parameters

bool — Whether to enable the absolute values monitoring.

- false — Disable
- true — Enable

Syntax 4

void **FTReached**(
)

Parameters

void — No parameter for cancelling the stop condition.

Return

void No return

25.2.12 Condition()

Set the stop condition of the conditional expression.

Syntax 1

void **Condition**(

bool or ?

)

Parameters

bool or ? The conditional can be true/false or a bool return of the statement.

Return

void No return

Syntax 2

void **Condition**(

)

Parameters

void No parameter for cancelling the stop condition.

Return

void No return

25.2.13 Start()

Start the force control motion.

Syntax 1

int **Start**(

bool,

bool

)

Parameters

bool Zero out force sensor before execution.

true Enable (default)

false Disable

bool Enable tool gravity compensation

true Enable

false Disable (default)

Return

int Return the result value after the force control motion stops.

0 Not Working

1 Working

2 Timeout

3 Distance reached

4	IO triggered
5	Resisted
6	Error
14	Over Speed
201	Digital IO triggered
202	Analog IO triggered
203	Variable
204	Force is comprehended
205	Allowable Position Tolerances
206	Motion Finish

Syntax 2

int **Start**(
    bool
)

Note

Same as syntax 1. Enabling the tool gravity compensation parameter will retrieve the parameter values of the associated device name in the force sensor setting of the project. Fill false if not retrieving the associated device name.

Syntax 3

int **Start**(
)

Note

Same as syntax 1. Fill true to zero out force sensor before execution. Enabling the tool gravity compensation parameter will retrieve the parameter values of the associated device name in the force sensor setting of the project. Fill false if not retrieving the associated device name.

25.2.14 Stop()

Stop the force control motion.

Syntax 1

int **Stop**(
)

Parameters

void	No parameter

Return

int	Return the result value after the force control motion stops.

- **Parameter Settings**

```
FTSensor fts1 = " TMFT300"    // Construct the device TMFT300.
Force fc1 = "fts1"            // Declare the force control variable and tether fts1 as the sensor name.

(1)
    fc1.Frame(3)                    // Set the force control coordinate as trajectory.
```

```
    fc1.Frame({517.5,-147.8,442.45,180,0,90})   // Set the force control coordinate as point (will
                                                overwrite the previous setting)
    fc1.Frame("P1")                             // Set the force control coordinate as point (will overwrite the
                                                previous setting)
    fc1.Reset()                                 // Reset all parameters (reserve tethering "fts1" as sensor name)
(2)
    fc1.Frame(3)
    fc1.Frame({517.5,-147.8,442.45,180,0,90})
    fc1.Frame("P1")
    fc1.FTSet(0, true, 5, 0)                        // Set axis FX with force control 5N with PID 0.
    fc1.FTSet(1, true, 6, 1)                        // Set axis FY with force control 6N with PID 1.
    fc1.FTSet(2, true, 7, 3)                        // Set axis FZ with force control 7N with PID 3.
    fc1.FTSet("FZ", true, 8)                    // Set axis FZ with force control 8N with PID 2. (will overwrite
                                                the previous FZ setting)
    fc1.Reset()                                 // Reset all parameters (reserve tethering "fts1" as sensor name)
(3)
    fc1.Frame(1)                                // Set the force control coordinate as tool.
    fc1.StopDuration(300)                       // Set the duration of compliance stop. to 300ms
    // Force and torque control
    fc1.Distance(1000)                              // Set moving distance to 1000mm
    fc1.FTSet("FZ", true, 5)                        // Set axis FZ with force control 5N
    // Stop conditions
    fc1.Timeout(10000)                              // Set timeout to 10000ms
    fc1.AllowPosTol(100)                            // Set the tolerant error to 100mm
    fc1.DInput("ControlBox", 0, "H")                // When ControlBox DI0 is High
    fc1.AInput("ControlBox", 0, ">=", 3.3)          // When ControlBox AI0 is greater than or equal to 3.3V
    fc1.FTReached(2, true, 1)                   // Axis FZ satisfies 1N
    fc1.FTReached("FZ", true, 2)                // Axis FZ satisfies 2N (will overwrite the previous FZ setting)
    fc1.FTReached(true)                         // Enable the absolute value monitoring
    int count = 0
    fc1.Condition(count > 100)                  // conditional expression
    fc1.Reset()                                 // Reset all parameters (reserve tethering "fts1" as sensor name)
```

- **SetPoint F/T Operation Mode**

SetPoint mode applies mainly to the robot touching the target with force control.

```
FTSensor fts1 = " TMFT300"
Force fc1 = "fts1"
(1)
    PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
    fc1.Distance(100)                           // Set moving distance to 100mm
    fc1.FTSet("FZ", true, 5)                    // Set axis FZ with force control 5N
    fc1.Start()                                 // Start the force control motion. Zero out force sensor before
                                                execution.
    //  Set axis FZ with force control 5N and the moving distance of 100mm, and the robot will move along
        with the Z-direction. The robot stops moving once it satisfies the moving distance. However, the
        motion is still under the force control, namely in the function.
```

(2)

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
fc1.FTSet("FZ", true, 5)              // Set axis FZ with force control 5N
fc1.AllowPosTol(80)                   // The stop condition of the tolerant position error.
int re = fc1.Start()                  // Start the force control motion. Zero out force sensor before
                                      execution.
//  Set axis FZ with force control 5N, and the robot will move along with the Z-direction and monitor the
    stop conditions concurrently. By satisfying the stop condition, the robot stops moving once it reaches
    within the tolerant position error, stops the force control motion, exits the function, and returns the
    result value.
```

(3)

```
PTP("JPP",{0,0,90,0,90,0},50,200,0,false)
fc1.Frame(1)                          // Set the force control coordinate as工具
fc1.StopDuration(300)                 // Set the duration of compliance stop.to 300ms
// Force and torque control
fc1.Distance(200)                     // Set moving distance to 200mm
fc1.FTSet("FZ", true, 5)              // Set axis FZ with force control 5N
// Stop conditions
fc1.Timeout(10000)                    // Set timeout to 10000ms
fc1.AllowPosTol(1000)                 // Set the tolerant error to 1000mm
fc1.DInput("ControlBox", 0, "H")      // When ControlBox DI0 is High
fc1.AInput("ControlBox", 0, ">=", 3.3) // When ControlBox AI0 >= 3.3V
int count = 0
fc1.Condition(count > 100)            // conditional expression
int re = fc1.Start()                  // Start the force control motion. Zero out force sensor before
                                      execution.
//  The robot stops moving once it satisfies the moving distance. However, the motion is still under the
    force control, and the system monitors the stop conditions continuously. Not until any stop conditions
    are comprehended will the force control motion be stopped, the function exit, and the result values
    after stopping be returned.
```

● Trajectory F/T Operation Mode

Trajectory mode applies mainly to the robot touching the target with robot base position control and force control.

```
FTSensor fts1 = " TMFT300"
Force fc1 = "fts1"
(1)
    fc1.FTSet("FZ", true, 2)          // Set axis FZ with force control 2N
    fc1.Trajectory("FTSubflow0")      // Set FTSubflow0 as the trajectory path. (Use in flow projects only.)
    int re = fc1.Start()              // Start the force control motion. Zero out force sensor before
                                      execution.
    //  Suppose FTSubflow0 comes with a few point nodes to finish.
    //  Set axis FZ with force control 2N and the trajectory path as the subflow FTSubflow0. The robot
        follows the nodes in the subflow to control and with force control concurrently. When the subflow
```

ends, it stops the force control motion, exits the function, and returns the result value.

(2)

```
fc1.FTSet("FZ", true, 2)          // Set axis FZ with force control 2N
fc1.Frame(3)                      // Set the force control coordinate as trajectory
fc1.Trajectory("FTSubflow0")      // Set FTSubflow0 as the trajectory path. (Use in flow projects only.)
int re = fc1.Start()              // Start the force control motion. Zero out force sensor before
                                  execution.
//    Suppose FTSubflow0 comes with a few point nodes to finish.
//    Set axis FZ with force control 2N and the trajectory path as the subflow FTSubflow0. The robot
      follows the nodes in the subflow to control and with force control concurrently. When the subflow
      ends, it stops the force control motion, exits the function, and returns the result value.
```

(3)

```
fc1.FTSet("FZ", true, 2)          // Set axis FZ with force control 2N
fc1.Frame(1)                      // Set the force control coordinate as tool
fc1.Trajectory("FTSubflow1")      // Set FTSubflow1 as the trajectory path. (Use in flow projects only.)
// Stop conditions
fc1.Timeout(10000)                // Timeout is invalid in the trajectory mod.
fc1.AllowPosTol(1000)             // Set the tolerant error to 1000mm
fc1.DInput("ControlBox", 0, "H")      // When ControlBox DI0 is High
fc1.FTReached("FZ", true, 2)      // Axis FZ satisfies 2N
fc1.FTReached(true)               // Enable the absolute value monitoring
int re = fc1.Start()              // Start the force control motion. Zero out force sensor before
                                  execution.
//    Suppose FTSubflow1 comes with a few point nodes to loop the loop.
//    Set axis FZ with force control 2N and the trajectory path as the subflow FTSubflow1. The robot
      follows the nodes in the subflow to control and with force control concurrently. Since the subflow is
      looping the loop, the robot motion, the force control, and the stop condition monitoring keep on. Not
      until any stop conditions are comprehended will the force control motion be stopped, the the function
      exit, and the result values after stopping be returned.
```

(4)

```
define
{
    FTSensor fts1 = " TMFT300"
    Force fc1 = "fts1"
    int count = 0
}
main
{
    fc1.FTSet("FZ", true, 1, 0)       // Set axis FZ with force control 8N with PID 0
    fc1.Frame(1)                      // Set the force control coordinate as tool
    fc1.Trajectory(FTMotion())//Set FTMotion() customized function as the trajectory path.
    // Stop conditions
    fc1.Timeout(10000)                // Timeout is invalid in the trajectory mode.
    fc1.AllowPosTol(1000)             // Set the tolerant error to 1000mm
    fc1.DInput("ControlBox", 0, "H")      // When ControlBox DI0 is High
    fc1.FTReached("FZ", true, 2)      // Axis FZ satisfies 2N
```

```
        fc1.FTReached(true)             // Enable the absolute value monitoring
        fc1.Condition(count++ > 200000)  // conditional expression
        int re = fc1.Start()
                                        // Start the force control motion. Zero out force sensor before
                                        execution.
        Display(re)
}
void FTMotion()
{
        while (true)
        {
                PTP("JPP",{15,0,90,0,90,0},50,200,100,false)
                PTP("JPP",{15,0,75,0,90,0},50,200,100,false)
                PTP("JPP",{-15,0,75,0,90,0},50,200,100,false)
                PTP("JPP",{-15,0,90,0,90,0},50,200,100,false)
                Sleep(10)
        }
}
//      Set axis FZ with force control 1N, PID 0, and the trajectory path as FTMotion() customized function.
        The robot follows the contents of FTMotion() to control and with force control concurrently. Since this
        function is looping the loop, the robot motion, the force control, and the stop condition monitoring
        keep on. Not until any stop conditions are comprehended will the force control motion be stopped, the
        function exit, and the result values after stopping be returned.
```

Revision History Table

Revision	Date	Description
00	November, 2025	● Updated descriptions of returns of the random() function ● Added Env in Parameterized objects ● Added ExecText() and ExecFile() functions ● Added RedirectToProject() function ● Added inversekin(), forwardkin(), and joint2pose() functions

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