

# NetwoRC provider

DENSO Robot

Version 1.2.19

User's guide

October 13, 2015

【Remarks】

**【Revision history】**

| Version | Date                     | Content                                                                                           |
|---------|--------------------------|---------------------------------------------------------------------------------------------------|
| 1.0.0   | 2006-05-11               | First edition.                                                                                    |
| 1.0.1   | 2006-07-17               | @n, ROTATE pose option, ST_* commands were supported.                                             |
| 1.0.2   | 2006-08-31               | SYSSTATE, Pose Data Type Transformation, Conveyer Tracking Commands were supported.               |
| 1.0.3   | 2006-09-13               | POSEDATA type was supported.                                                                      |
| 1.0.4   | 2006-10-16               | Trouble Shooting was added.                                                                       |
| 1.0.5   | 2006-12-09               | A “Len” option of I/O variable was added                                                          |
| 1.1.0   | 2007-07-12               | Servo Log Commands were added, RC5 was supported.                                                 |
| 1.1.1   | 2007-08-10               | MyIP option was added.                                                                            |
| 1.1.2   | 2007-11-21               | TORetry option was added.                                                                         |
| 1.2.0   | 2008-01-14               | Extended-joints were supported.                                                                   |
| 1.2.1   | 2008-01-21               | Error code table was added.                                                                       |
| 1.2.2   | 2008-06-18               | An high path accuracy command was added.                                                          |
| 1.2.3   | 2008-07-02               | Minor upgrade.                                                                                    |
| 1.2.4   | 2008-08-22               | FIGAPRP, FIGAPRL were supported.                                                                  |
| 1.2.5   | 2008-09-30               | Minor upgrade.                                                                                    |
| 1.2.6   | 2008-11-21               | Variable name with ‘*’ (ex. I[*]) and UDP local port option were added.                           |
| 1.2.7   | 2009-06-12               | Collision Detection Commands was supported.                                                       |
| 1.2.8   | 2009-07-03               | Tips were added. WDIn and WDOut were supported.                                                   |
| 1.2.9   | 2009-07-07               | Variable time stamp (Microsecond property) was supported.                                         |
| 1.2.10  | 2010-02-11               | Mini I/O All-general was supported. Error code was added.                                         |
| 1.2.11  | 2010-05-21               | CtrlChk option was added.                                                                         |
| 1.2.12  | 2010-11-17               | Correct Execute command name.                                                                     |
| 1.2.13  | 2011-01-11               | “Transferring PAC program” upgrade.                                                               |
| 1.2.14  | 2011-02-01               | “caoRobot” Commands upgrade.                                                                      |
| 1.2.15  | 2011-04-05               | Correct Hardware version.                                                                         |
| 1.2.16  | 2011-04-21               | Non-stop motion calculator option was added.                                                      |
| 1.2.17  | 2011-05-16               | @ERROR_CODE_HEX was added.                                                                        |
| 1.2.18  | 2011-05-26<br>2012-07-17 | The Bundle connection limitation (max. 3) was abolished.<br>Document versioning rules was changed |
| 1.2.19  | 2015-10-13               | @ERROR_LEVEL was added                                                                            |

**【Hardware】**

| Model | Version            | Notes                                                         |
|-------|--------------------|---------------------------------------------------------------|
| RC7   | Ver2.330 or higher | “ORiN” option (1214) is required.                             |
| RC5   | Ver1.998 or higher | “ORiN” option (1213) is required. See Appendix D for details. |

**【Attention】**

**The maximum number with which NetwoRC can be connected<sup>1</sup> at a time is 79.**

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<sup>1</sup> Connected Number = Number of instances of NetwoRC providers = Number of objects made with CaoWorkspace::AddController

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## 1. Introduction

This document describes external specifications of the CAO provider for NetwoRC controller (RC7) of the DENSO robot. In this document, CAO provider (CaoProvRoboTalk.dll) is called as NetwoRC provider. The NetwoRC provider implements all interfaces defined in the CAO provider specification.

This document describes the NetwoRC provider specifications on connection parameters, system variables, user variables, files and original enhancement.

The dependency of the NetwoRC controller's model and version is described in the next table used as Sign in this document.

**Table 1-1 NetwoRC controller's model and version**

| Controller |               | Sign                                                                                               | Explanation                                              |
|------------|---------------|----------------------------------------------------------------------------------------------------|----------------------------------------------------------|
| Model      | Version       |                                                                                                    |                                                          |
| RC7M       | 2.330 or more |  <b>2.330</b>     | If the controller version is 2.330 or more, it is valid. |
| -          | -             |  <b>RobSlave</b> | "RobSlave.pac" program need to be executed commands.     |



**All global variables (I, F, D, V, P, J, T, S) from [0] to [9] have been reserved with the system.**

**Please do not access these variables in the user's program.**

## 1.1. Outline

The NetwoRC provider is CAO provider that absorbs RC7 dependant part and offers the function defined by the CAO provider interface specifications. The file format is DLL (Dynamic Link Library), and it is dynamically loaded from CAO engine when it is used. To use NetwoRC provider, registry need to be manually registered according to the table below.

**Table 1-2 NetwoRC provider**

|                                    |                                |
|------------------------------------|--------------------------------|
| File name                          | CaoProvNetwoRC.dll             |
| ProgID                             | CaoProv.DENSO.NetwoRC          |
| Registry registration <sup>2</sup> | regsvr32 CaoProvNetwoRC.dll    |
| Remove registry registration       | regsvr32 /u CaoProvNetwoRC.dll |

A license key is required to use the CAO Engine module. Please refer to “License registration” section of [“ORiN2 SDK User’s Guide”](#).

NetwoRC provider communicates to the controller using RS232C or Ethernet, and the provider supports functions like controller variable read/write, PAC program invocation, and robot motion. ORiN supports various communications to connect to the robot controller, as shown in Figure 1-1. This provider supports the communication method shown in the red frame.

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<sup>2</sup>In case of installation from ORiN2 SDK, register and unregister operation is not required.

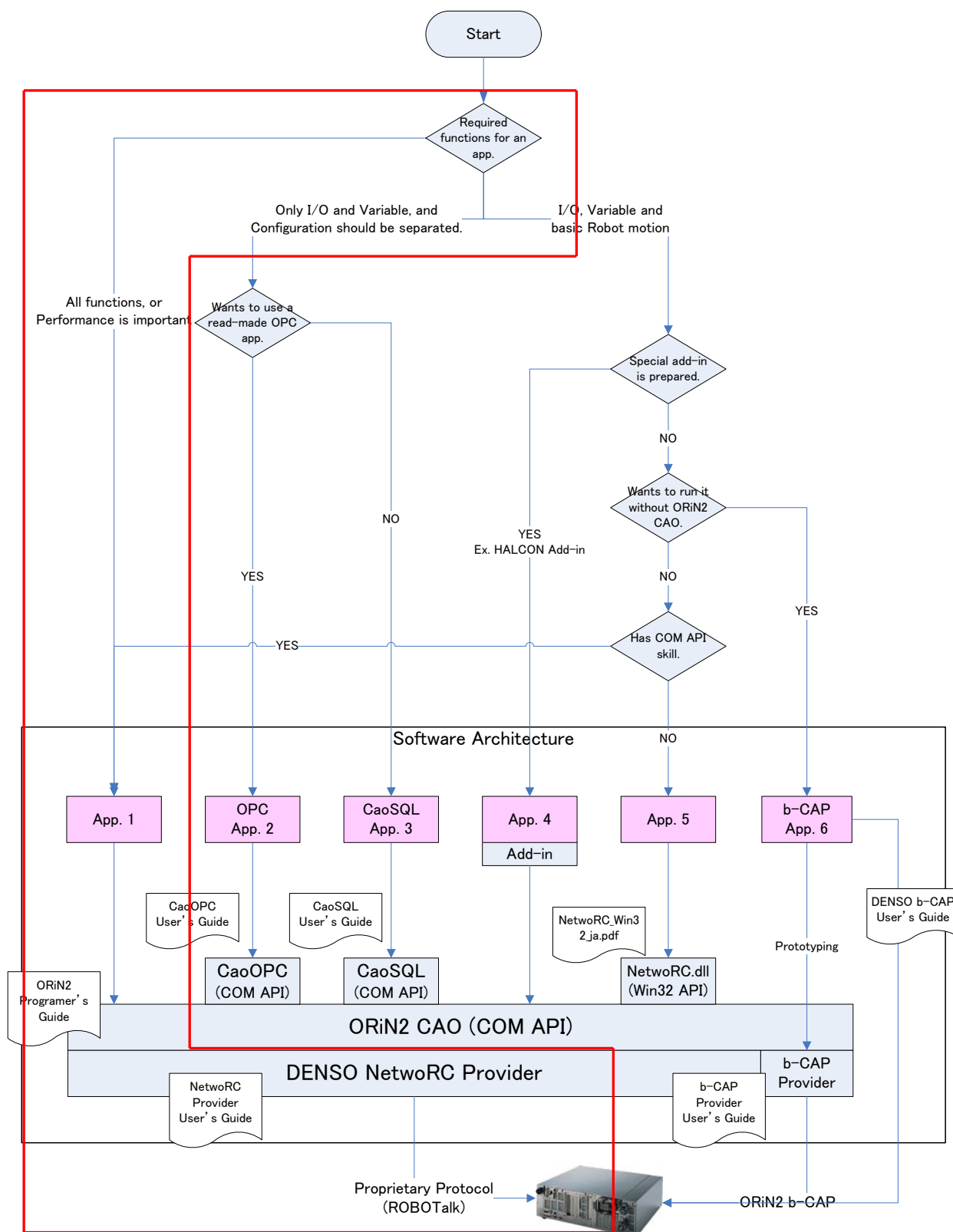


Figure 1-1 Robot connection

## 2. Setup

### 2.1. Emergency stop device position

A robot emergency stop switch should be prepared and set up near a robot operator before operating the robot, so that the switch can immediately stop the robot motion in an emergency situation.

The robot emergency stop switch should meet the following requirement.

- (1) The emergency stop switch should be red-colored.
- (2) After the emergency stop switch is activated, the switch should not return to normal (robot operating) position automatically or by other operator's careless action.
- (3) A robot emergency stop switch should be set up separately from the power switch.

The emergency stop device shall be in accordance with IEC 60204-1:2005, 10.7 and ISO 13850.

### 2.2. Controller setup

A robot controller need to be setup before is controlled by the NetwoRC provider. A teach pendant or a mini pendant is needed for the robot controller setup. Following is the procedure to setup the controller.

#### 2.2.1. Setup using a teach pendant

Setup a robot controller with a teach pendant according to the following procedure.

- (1) Set the robot controller to the manual mode.

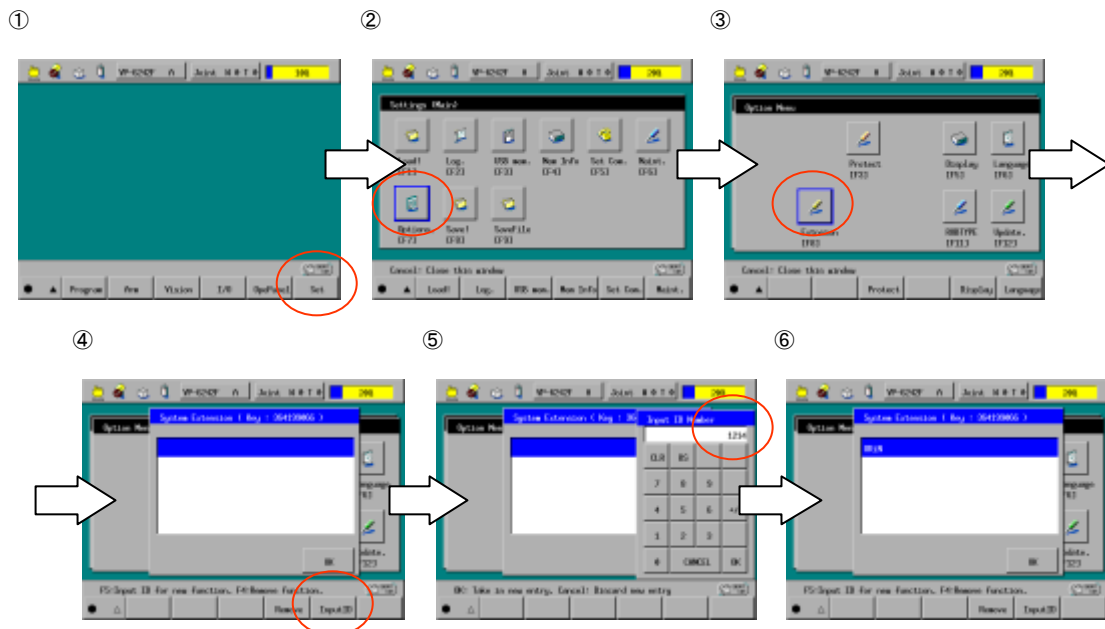
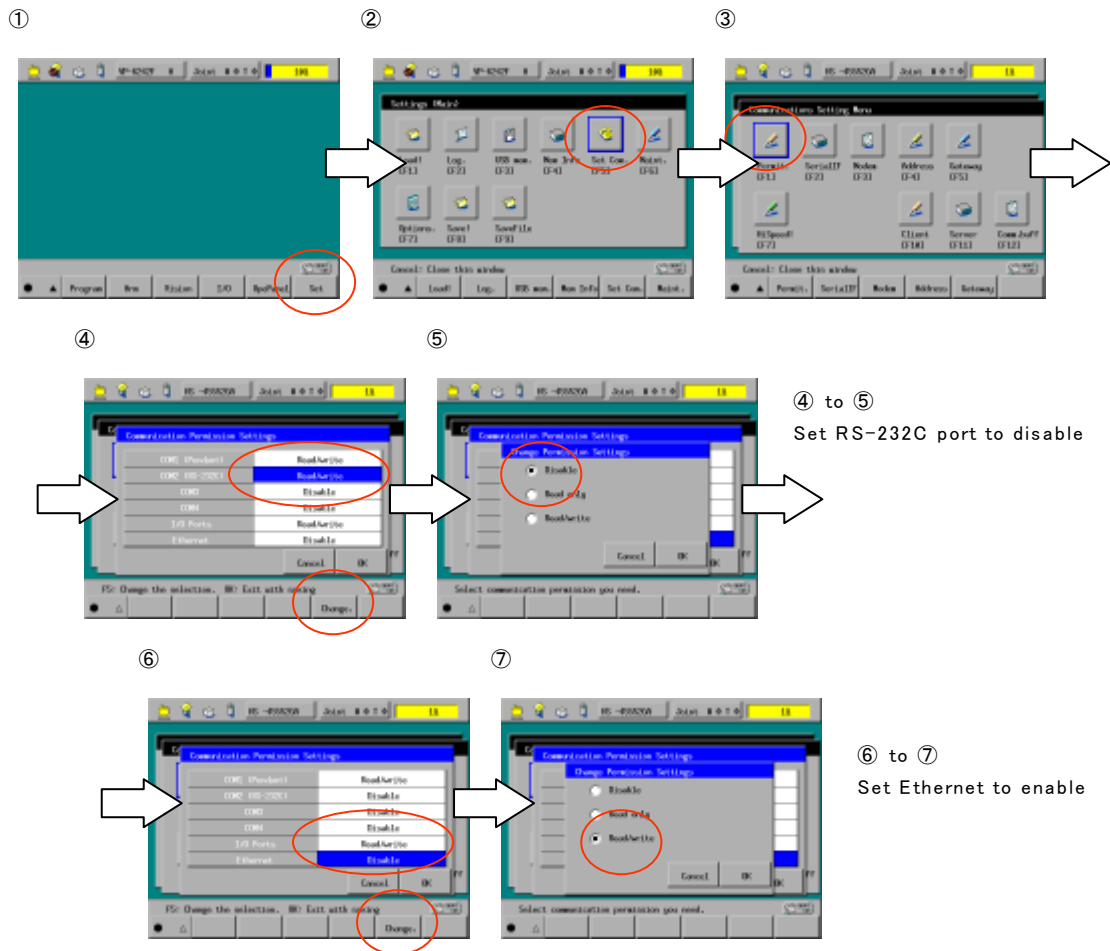


Figure 2-1 ORiN option activation

- (2) Set controller's communication permission. When you use Ethernet, Set "Read/Write" in the menu "Communications setting menu" => "Permit." When you use RS-232C, set "Read/Write" in the same menu



**Figure 2-2 Setting of communication permission**

- (3) Activate ORiN option. Select "Option" => Input password "1214" in the function expansion menu to activate "ORiN" option. <sup>3</sup> Input "1213" if robot controller is RC5.
- (4) To turn ON/OFF the motor of the robot, or to start programs from an ORiN application, it is necessary to set controller's executable token. Set the executable token to "Ethernet" by setting the "Communications setting menu" => "Ext.Run", and set IP address of client PC by "F4:IP set" menu afterwards when you use Ethernet as the connection method. Set the executable token to each COM port when you use RS232 C.

<sup>3</sup> By setting "ORiN" option, ORiN applications can freely access the variables and I/Os. Access the variables and I/Os after fully understanding the state and the content of the robot controller program etc. Especially, the changing the variables and I/Os might give the critical effect to the movement of the robot and the program.

In the internal automatic mode, when "ORiN" option is activated, the robot program stops if an error more than level 3 occurs. However, in external automatic mode, the robot program stops if an error more than error level 2 occurs. Therefore, when a robot is in external automatic mode, please be careful not to perform wrong operation or not to transmit a wrong command.

2.330

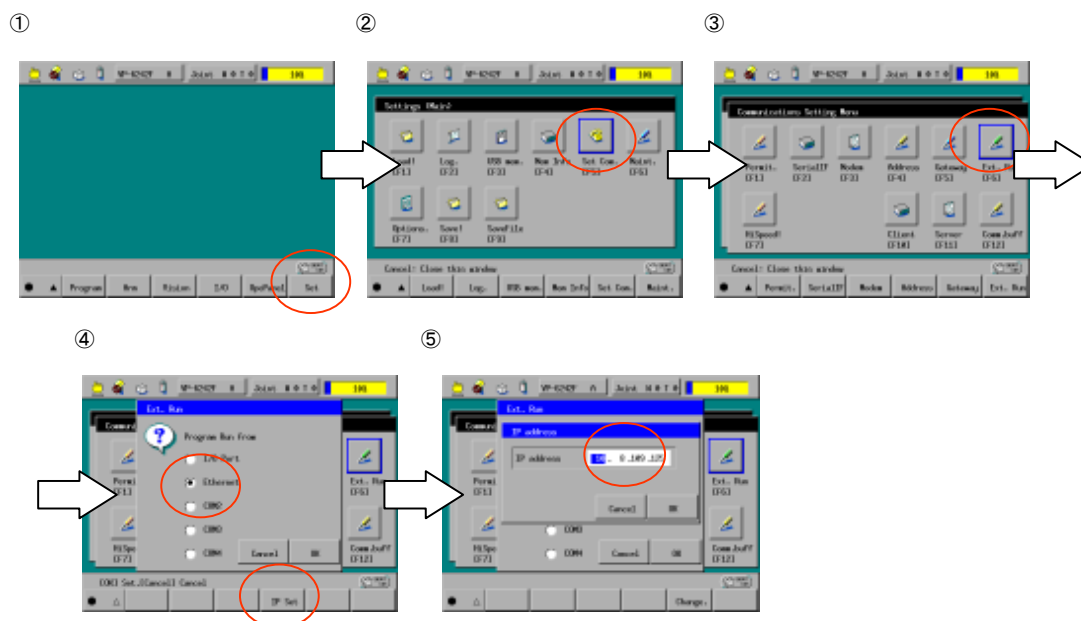


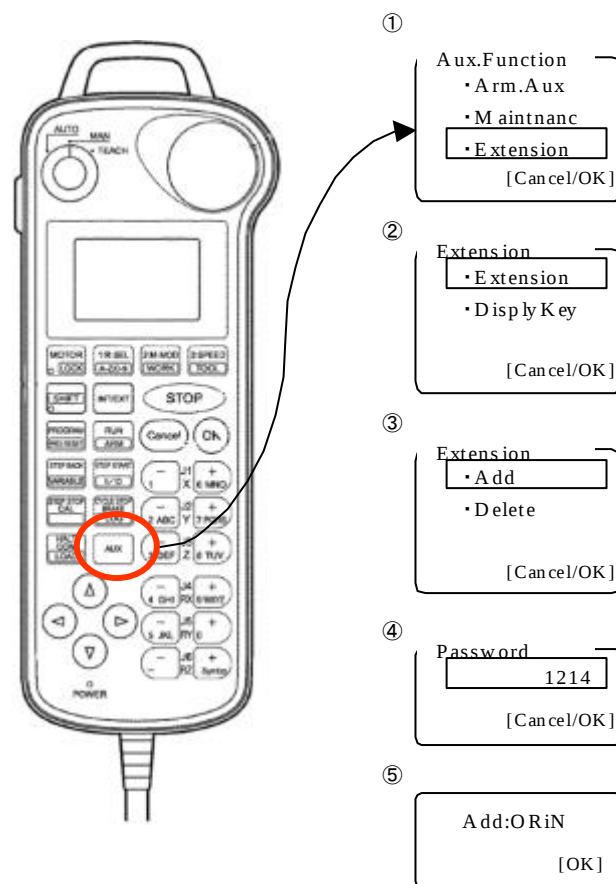
Figure 2-3 Settings of Executable token

### 2.2.2. Setup using the mini pendant

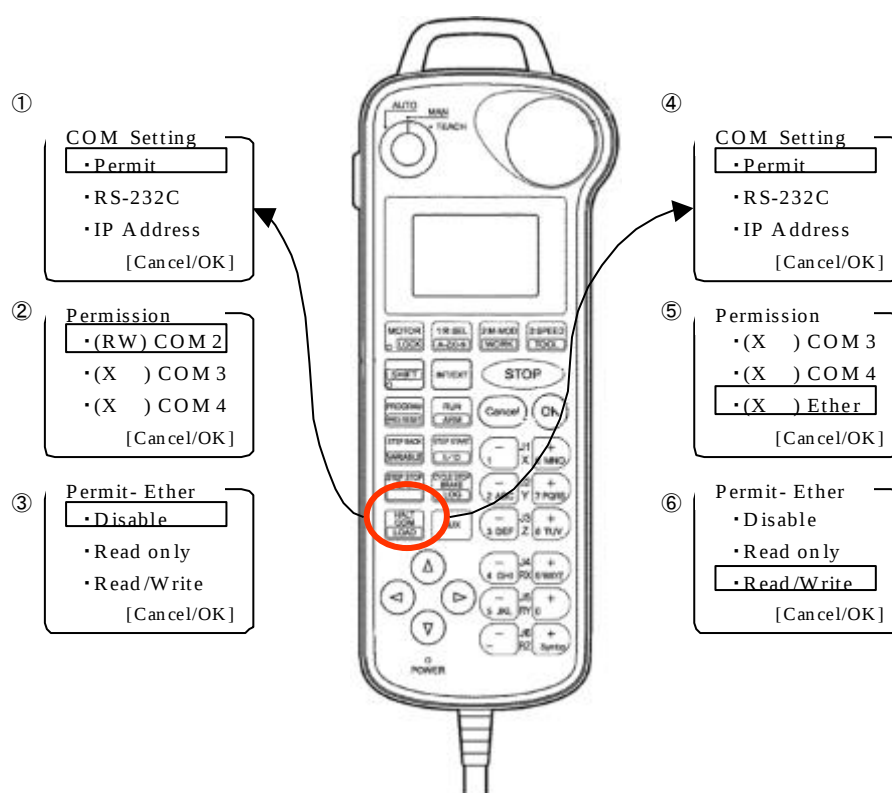
2.330

Setup a controller with a mini pendant according to the following procedure.

- (1) Set a robot controller to the manual mode.
- (2) Activate ORiN option. [Aux Function] => [Extension] => [Extension] => Input "1214" with Add and make "ORiN" effective.<sup>3</sup>

**Figure 2-4 ORiN option activation**

- (3) Set robot controller's communication permission. When you use Ethernet, go to COM Setting of mini pendant => Set R/W to Ethernet with Permit. When you use RS232C, set R/W to appropriate COM port.



**Figure 2-5 Setting of communication permission**

- (4) To turn ON/OFF the motor of the robot, or to start programs from an ORiN application, it is necessary to set controller's executable token. When Ethernet is used for communication, go to COM menu of mini pendant and set the executable token to Ethernet in [Ext Run], and also set IP address of client PC in [Client IP] menu. Set the executable token to appropriate COM port when you use RS232 C.

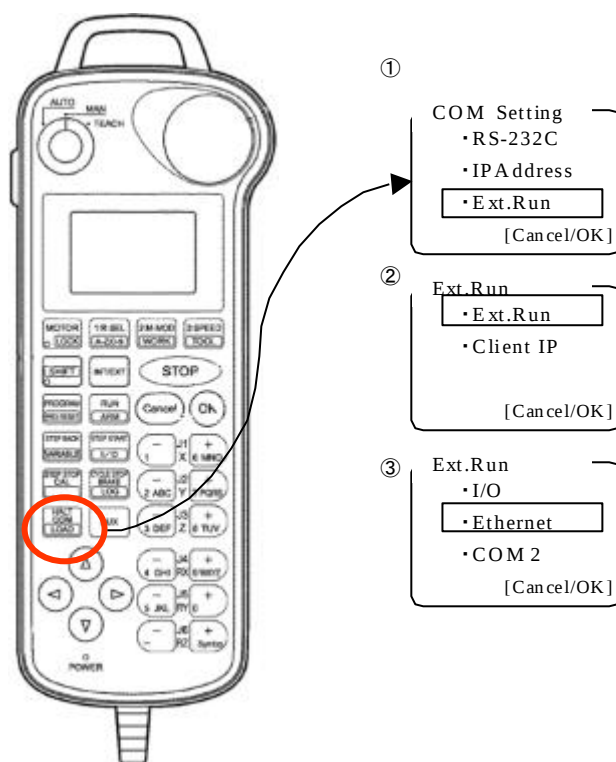


Figure 2-6 Setting of Executable token

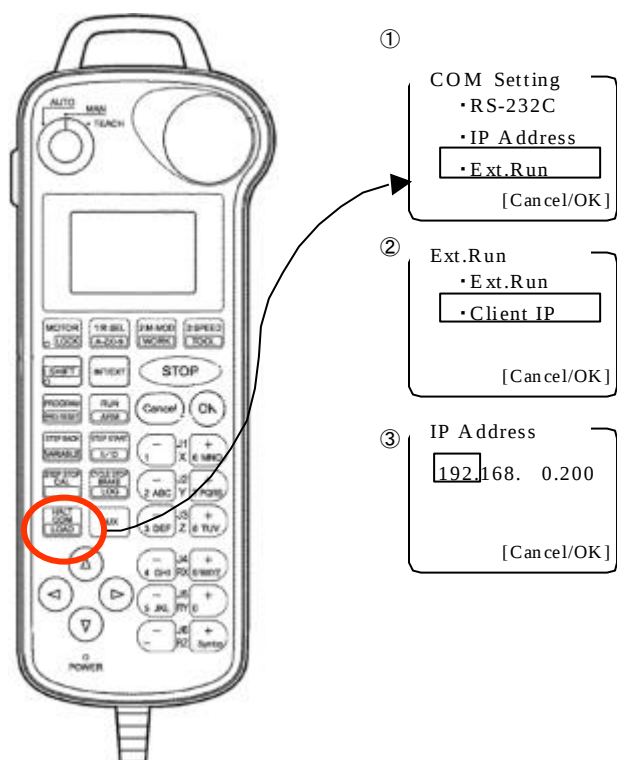


Figure 2-7 Input of IP address of client PC

## 2.3. Treatment of special I/O port

**2.330**

DENSO robot controller has a lot of system input signals.

To operate robot from PCs connected to the robot controller using ORiN, “Step stop (All tasks) signal” and “Instantaneous stop signal” need to be set to enable robot program execution.

Connector assignment and pin assignment of “Step stop (All tasks) signal” and “Instantaneous stop signal” are different depending on the robot controller configuration and I/O assignment. Please confirm the robot controller configuration to make correct I/O treatment to enable robot program execution.

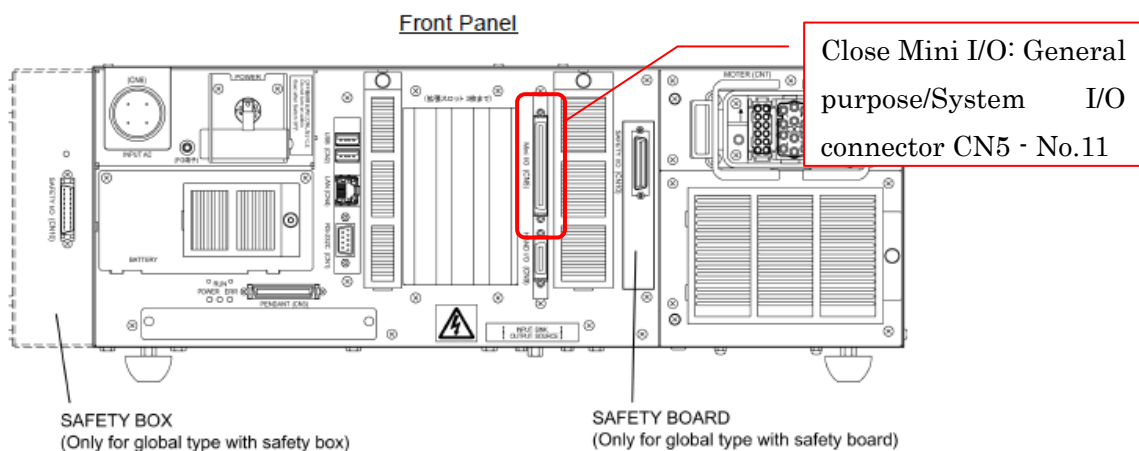
[Note 1] The I/O treatment is not necessary for RC5, because these versions of software does not support running robot program using ORiN.

[Note 2] The I/O treatment is not necessary, if ORiN is used only to access variables or files, and if ORiN is NOT used to control robot motion or robot program (PAC).

### 2.3.1. I/O treatment for standard configuration controller (without I/O extension board)

Please close Mini I/O general purpose / system I/O connector CN5 – terminal No.11.

By closing the signal, Step stop (All tasks) signal (port number 0) becomes ON, and robot and program execution is enabled.



**Figure 2-8 Step stop (All tasks) treatment**

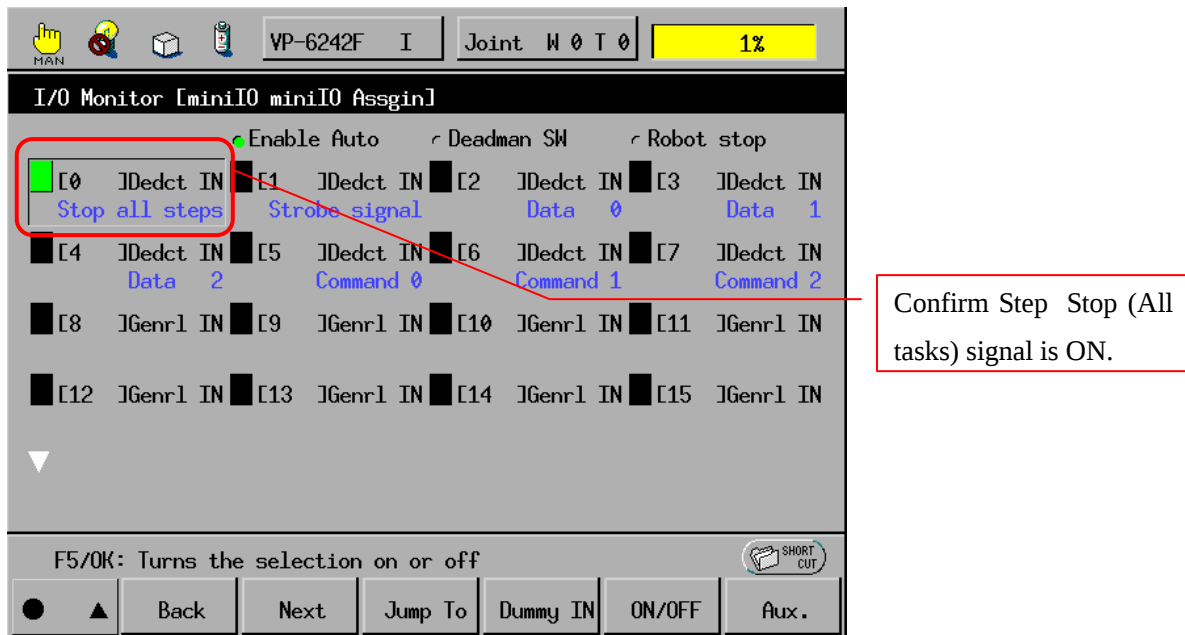


Figure 2-9 Signal confirmation after I/O treatment

This type of I/O does not have Instantaneous stop signal, so no treatment is necessary.

### 2.3.1.1. Mini I/O All general option

Mini I/O All-general option, available on Version 2.90 or later, is for robot system that does not require special I/O port assigned to mini I/O. By activating the option, all mini I/O ports are assigned as general I/O, and step stop signal wiring becomes not necessary.

To activate the option, setup a robot controller with a teach pendant according to the following procedure.

- (1) Set a robot controller to the manual mode.
- (2) To activate Mini I/O All-general option, select “Option” => “Function expansion” menu and input password “6319”.
- (3) Turn off and restart a robot controller.

[Note 1] By activating mini I/O all-general option, a special I/O input assignment of step stop signal is nullified, and the robot cannot be step-stopped by the I/O input.

[Note 2] By activating mini I/O all-general option, step stop wiring becomes not necessary. However, wirings for auto enable input and emergency stop input are still necessary even if the option is activated.

### 2.3.2. I/O treatment for controllers with I/O extension board

If a robot controller is configured with extension I/O board (parallel I/O, DeviceNet, CC-Link, PROFIBUS, etc.), please refer “Installation and maintenance guide” and “Options Manual – Part2: RC7M I/O extension

board”, and turn on “Step stop (All tasks) signal” and “Instantaneous stop signal”.

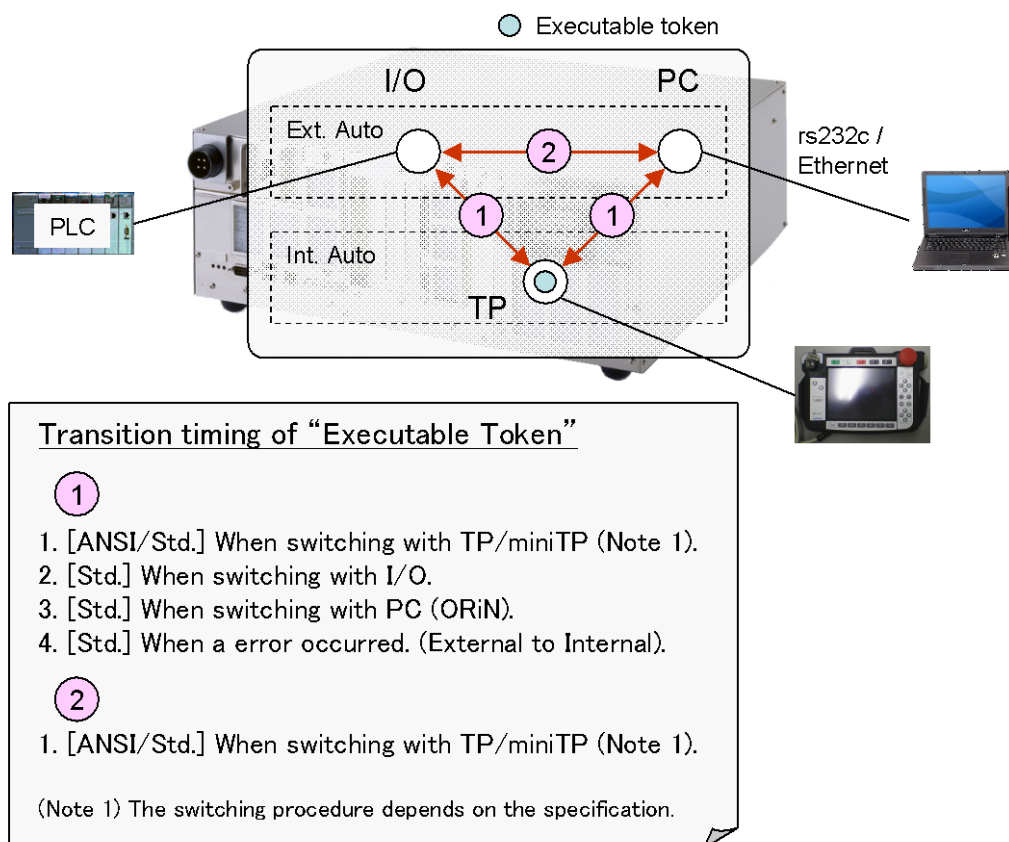
## 2.4. Robot controller's Executable Token

 **2.330**

### 2.4.1. Basic knowledge concerning robot controller's Executable Token

It is necessary to set the executable token for turning ON/OFF the motor or starting the program from the ORiN application. (Refer to 2.2.1 and 2.2.2). For the safety reason and to meet with “Single point of control” requirement, only the selected equipment can control a robot controller from the outside. Moreover, the robot controller becomes executable only in the external automatic mode as for turning ON/OFF the motor and starting the task from the ORiN application.

The executable token changes as shown in the following figures.



**Figure 2-10 Transition of executable token**

### 2.4.2. Notes in ANSI type robot controller

As previously stated, turning ON/OFF the motor and starting a program from the ORiN application is possible only if the controller is in the external automatic mode.

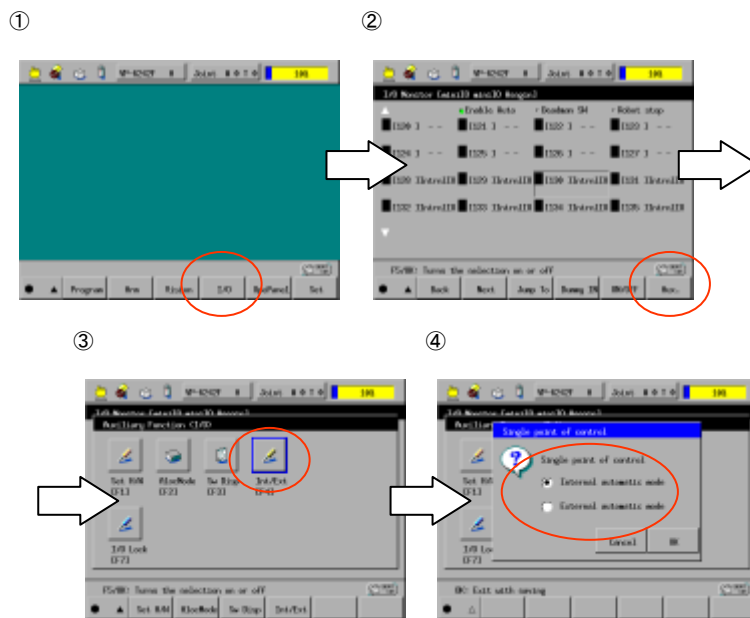
For the robot controller of the ANSI type, please note that you need to go to “I/O Auxiliary Function” – “single point of control” menu and select “External automatic operation” to change the robot controller to external automatic mode.

Following is the procedure to select external automatic mode in ANSI type controller. (Note: The ext button

on RobMaster does not work for ANSI type robot controllers.)

#### (4) Mode selection procedure using the teach pendant

After the following procedure is completed and robot is set to automatic mode, robot mode will be changed to the selected (internal or external) automatic mode.



**Figure 2-11 Internal/external automatic mode selection by teach pendant**

#### (5) Mode selection procedure using the mini pendant

After the following procedure is completed and robot is set to automatic mode, robot mode will be changed to the selected (internal or external) automatic mode.

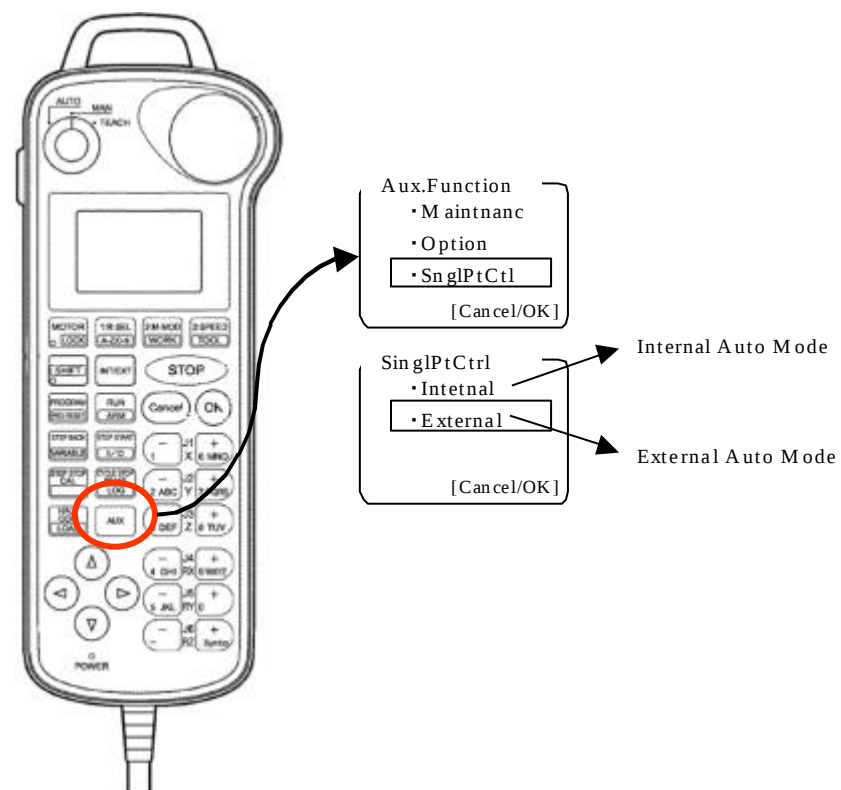


Figure 2-12 Internal/external automatic mode selection by mini pendant

## 2.5. Transferring PAC program

 **2.330**

To execute robot motion commands (refer to Table 4-8) with NetwoRC provider, following PAC programs, RobSlave.pac, RobSlave.h and UserExtention.pac, need to be sent to the robot controller and need to be executed.

To transfer PAC program to a robot controller, Using RobMaster.exe tool included ORiN SDK.

Mini pendant (mini TP) or Teach pendant (TP) is necessary for these method.

RobMaster.exe<sup>4</sup> is a tool to show robot controller status and to control RobSlave task directly from PC, and the tool program is stored in NetwoRC provider installation folder.

<OriN2 installation folder>\CAO\ProviderLib\DENSO\NetwoRC\Bin

Start RobMaster.exe and follow this procedure to setup the controller.

1. Start robot controller, and change to [manual] mode.
2. Start RobMaster.exe program.  
Start > All Programs > ORiN2 > CAO > ProviderLib > RobMaster
3. Press [Connect] button to connect the program to the robot controller.
4. Press [Setup] button of RobMaster.exe and follow the instructions to send necessary PAC programs to the robot controller.

## 2.6. Introduction of RobMaster

 **2.330**

Bundled tool RobMaster is connected to a robot controller, and offers the following function.

1. Set up a robot controller to be used with ORiN.
2. Start and stop the controller's RobSlave task.
3. Turn on and off the motor power of the controller.
4. Display robot controller error status and clear error.
5. Display robot controller statuses.

Following is the introduction of RobMaster functions.

<sup>4</sup> <ORiN2 SDK install folder>\CAO\ProviderLib\DENSO\NetwoRC\Bin\RobMaster.exe

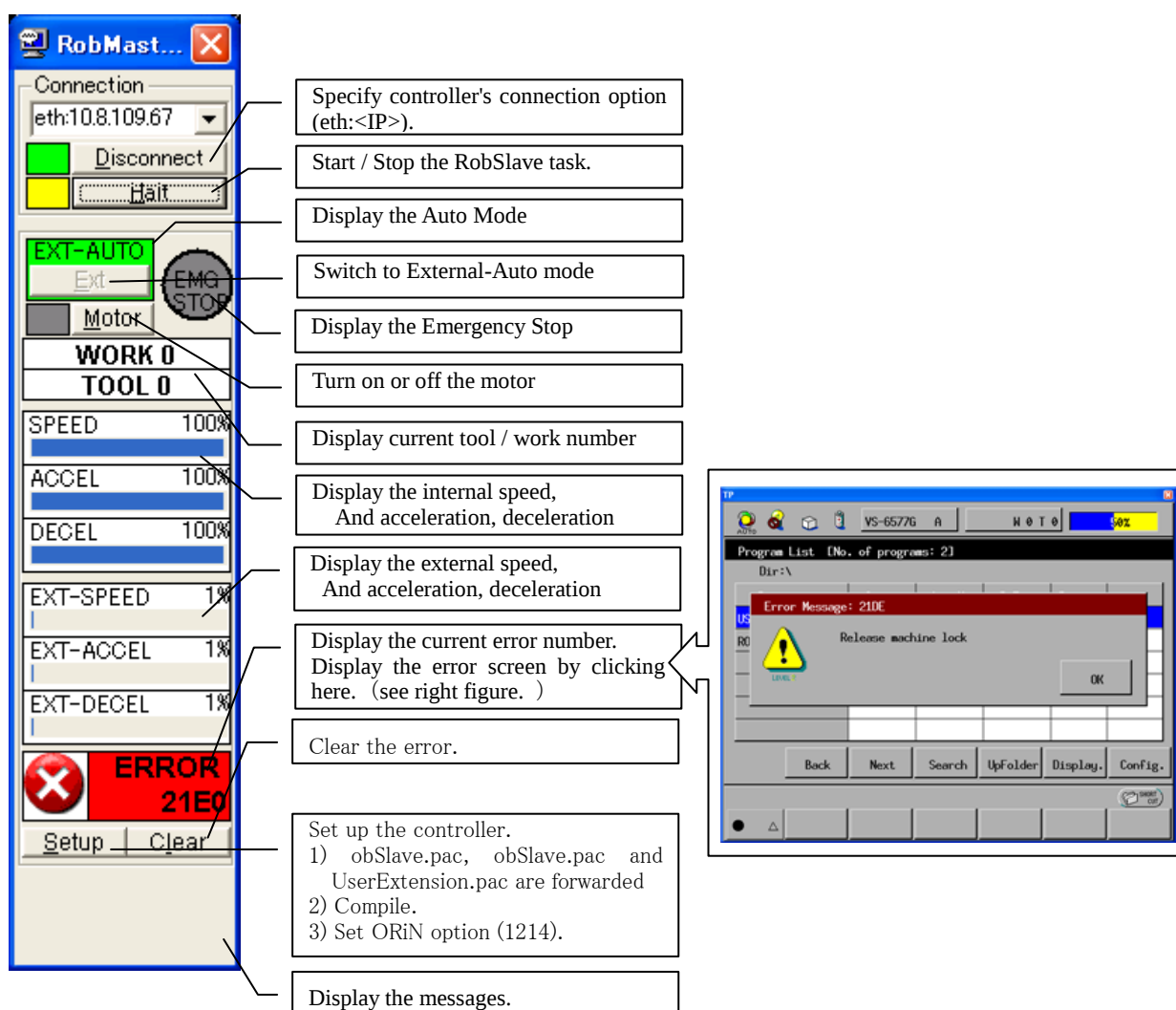


Figure 2-13 Function introduction of RobMaster

## 3. Programming with NetwoRC provider

### 3.1. Connection

To control robot with NetwoRC provider, communication between an ORiN installed PC and the robot controller should be established with RS232C or Ethernet. Some commands also require the robot controller setup. For details of setup, please refer chapter 2, and for details of commands, please refer chapter 4.



Figure 3-1 Robot connection

The developed program uses NetwoRC provider to communicate with the robot controller, by generating NetwoRC proprietary communication (RoboTALK) packet. An special program called RobSlave runs on the controller for handshaking and operating robot. For details please refer chapter 5.

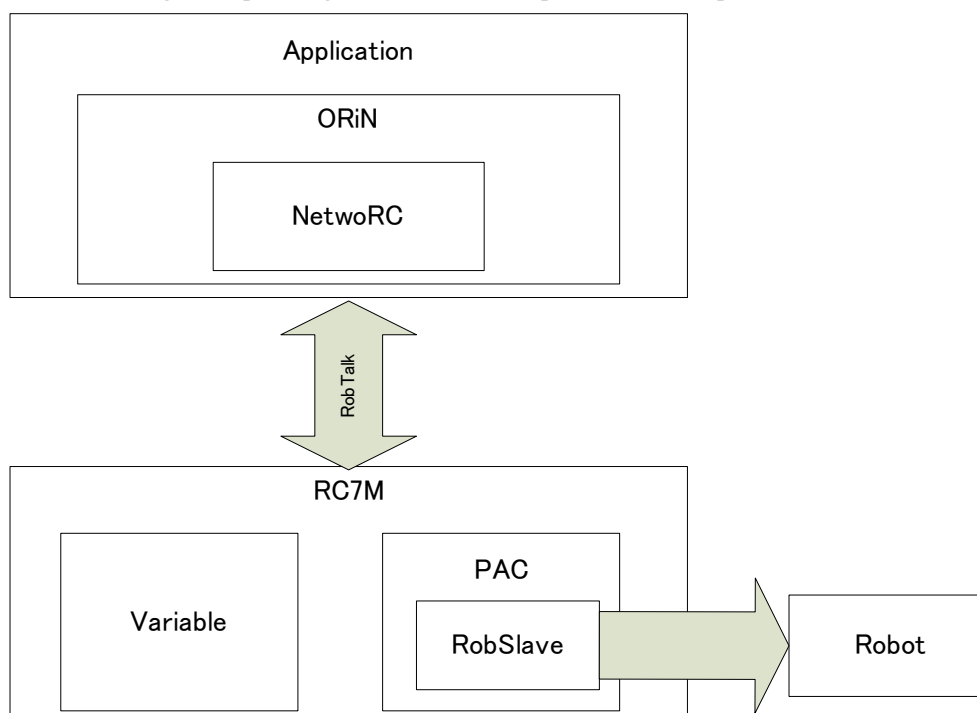


Figure 3-2 Outline of programming

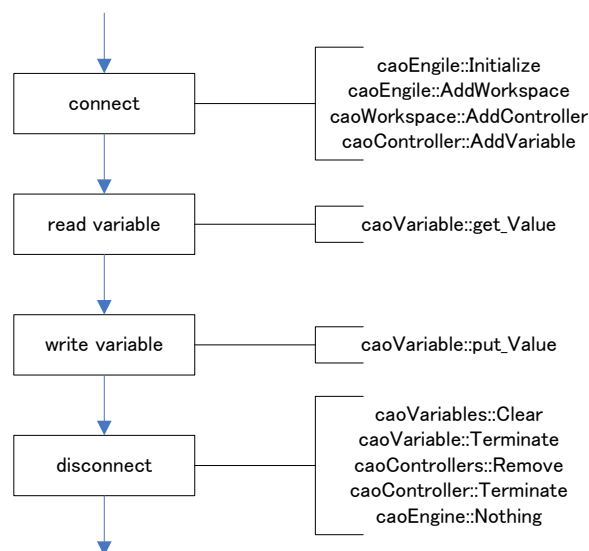
NetwoRC provider establishes communication between the PC and the robot controller by the following procedure.

- Create CaoEngine
- Create CaoWorkspace
- Create CaoController

After the communication is established, variables in the controller will be access by creating CaoVariable object, and robot motions will be initiated by creating CaoRobot object. Examples in the following section explain the procedure of robot programming.

### 3.2. Variable Read/Write

Figure 3-3 shows the procedure to read and write variables.



**Figure 3-3 Read and write variable**

#### 3.2.1. Connection

Following is the procedure to establish connection to the robot controller.

- (1) Create a variable to store object

CaoEngine object, CaoWorkspace object and CaoController object are required to establish communication to the robot controller. CaoWorkSpace need not prepare a variable if it is directory acquired from CaoWorkspaces. CaoVariable object is also necessary to access to variables. Following is a code example in VB6.

```

Dim g_eng as CaoEngine      ' CaoEngine object variable
Dim g_wrks as caoWorkspace  ' CaoWorkspace object variable
Dim g_ctrl as CaoController  ' CaoController object variable
Dim g_val as CaoVariable     ' CaoVariable object variable
  
```

- (2) Create CaoEngine object

CaoEngine object is created with New keyword..

```
Set g_eng = New CaoEngine ' CaoEngine object creation
```

(3) Acquire or create CaoWorkspace object

When created, CaoEngine object automatically creates one Caoworkspaces object and one Caoworkspace object. The next sample program uses the automatically created workspace. Following is a code example of creating new CaoWorkspace object.

```
g_wrks = g_ctrl.Addworkspace("NewWrks", "")
```

(4) Create CaoController object

To create a CaoController object, specify the provider name and its parameters. NetwoRC provider specifies destination controller IP address as an option. Following is an example code.

```
g_ctrl = g_wrks.AddController("RC", "CaoProv.DENSO.NetwoRC", "", "conn=eth:192.168.0.1")
```

(5) Create CaoVariable object

Create an object of CaoVariable for the accessed variable. Following is an example code of accessing the 10<sup>th</sup> element of P type variable.

```
g_val = g_ctrl.AddVariable("P10", "")
```

### 3.2.2. Read/Write Variabl

To read and write the connected variable value, use Value property of CaoVariable object. To read and write value, another variable with the suitable type for the connected variable should be prepared. Following is an example code.

```
Dim vntPotision as Variant
vntPotision = g_val.Value ' Read value
g_val.Value = Array(50, 50, 50, 0, 0, 0, -1) ' Write value
```

### 3.2.3. Disconnection

To disconnect from the controller, delete not only created object itself, but also delete the object from a collection class that manages the object. Following is an example code.

```
g_ctrl.Variables.Clear ' Delete all objects from CaoVariables
Set g_val = Nothing ' Delete CaoVariable
g_wrks.Controllers.Remove g_ctrl.Index ' Delete CaoController from CaoControllers
Set g_ctrl = Nothing ' Delete CaoCtonroller
g_eng.Workspaces.Remove g_wrks.Index ' Delete CaoWorkspace from CaoWorkspaces
Set g_wrks = Nothing ' Delete CaoWorkspace
Set g_eng = Nothing ' Delete CaoEngine
```

### 3.2.4. Sample program

Following is an example program written with VB6. IP and Port should be set to the value for the target controller. This sample program uses following value.

IP:192.168.0.1

Port:4112

#### List 3-1

#### Variable.frm

```

Dim g_eng As CaoEngine
Dim g_ctrl As CaoController
Dim g_val As CaoVariable

Private Sub Form_Load()
    Set g_eng = New CaoEngine

    ' connect RC : IP/Port setting depends on your RC setting.
    Set g_ctrl = g_eng.Workspaces(0).AddController("RC7", "caoProv.DENSO.NetwoRC", "",
"conn=eth:192.168.0.1:4112")

    ' variable name "I0150"
    Set g_val = g_ctrl.AddVariable("I0150", "")
End Sub

Private Sub Form_Unload(Cancel As Integer)
    ' destroy variable
    g_ctrl.Variables.Clear
    Set g_val = Nothing

    ' destroy controller
    g_eng.Workspaces(0).Controllers.Remove g_ctrl.Index
    Set g_ctrl = Nothing

    ' Destroy CaoEngine
    Set g_eng = Nothing
End Sub

Private Sub Command1_Click()
    ' read variable
    Text1.Text = g_val.Value
End Sub

Private Sub Command2_Click()
    ' write variable
    g_val.Value = Cbool(Text2.Text)
End Sub

```

### 3.3. Start and stop PAC program PAC

To start and stop PAC program, used the procedure described in Figure 3-4. The controller should be set to external auto mode to start PAC program. Also, the controller start right should be given to the IP address of the ORiN installed PC. For details, please refer chapter 2.4.

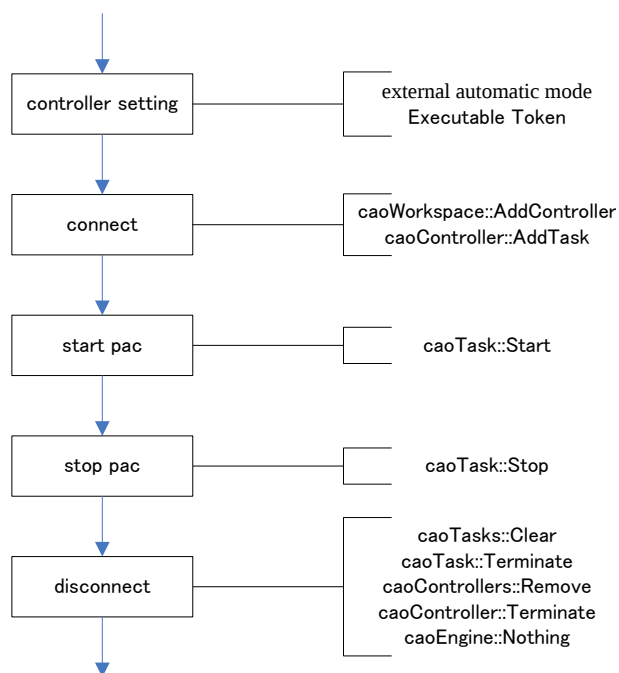


Figure 3-4 Start and stop pac program

### 3.3.1. Connection

Please refer 3.2.1 for the procedure of creating CaoController object. Create CaoTask object to start and stop PAC program. Following is an example code.

```
Dim g_task as CaoTask      ' A variable to store CaoTask
Set g_task = g_ctrl.AddTask("PRO01", "")
```

### 3.3.2. Start/Stop PAC program

To start and stop PAC program, use Start method and Stop method of CaoTask object. Following is an example.

```
g_task.Start 2      ' Continuous execution
g_task.Stop 3      ' Cycle stop
```

### 3.3.3. Sample Program

#### List 3-2 Task.frm

```
Dim g_eng As CaoEngine
Dim g_ctrl As CaoController
Dim g_task As CaoTask

Private Sub Command1_Click()
  g_task.Start 2
End Sub
```

```

Private Sub Command2_Click()
    g_task.Stop 3
End Sub

Private Sub Form_Load()
    Set g_eng = New CaoEngine

    ' connect RC : IP/Port setting depends on your RC setting.
    Set g_ctrl = g_eng.Workspaces(0).AddController("RC7", "caoProv.DENSO.NetwoRC", "",
"conn=eth:192.168.0.1")

    ' Task Name "PR01"
    Set g_task = g_ctrl.AddTask("PR01", "")
End Sub

Private Sub Form_Unload(Cancel As Integer)
    g_ctrl.Tasks.Clear
    Set g_task = Nothing

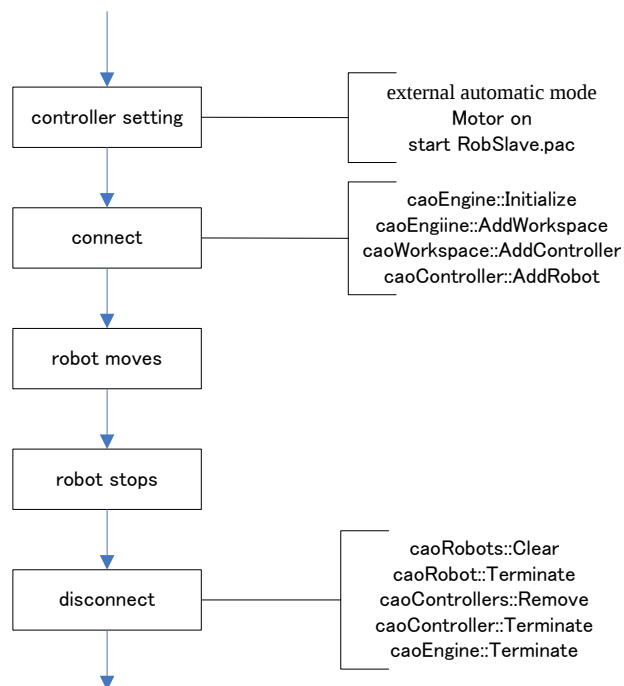
    g_eng.Workspaces(0).Controllers.Remove g_ctrl.Index
    Set g_ctrl = Nothing

    Set g_eng = Nothing
End Sub

```

### 3.4. Robot motion

To move robot, the controller should be set auto mode and RobSlave program should be started on the controller. For RobSlave, please refer to chapter 2.5. Motor power can be also controlled with NetwoRC provider. For details, please refer to CaoTask:Execute motor command in 4.2.39.



### 3-5 Robot Moves

#### 3.4.1. Connection

Please refer 3.2.1 for the procedure of creating CaoController object. To move robot, create CaoRobot object. Following is an example code.

```
Dim g_robot as CaoRobot      ' A variable to store CaoRobot object
Set g_robot = g_ctrl.AddRobot("Arm", "")
```

#### 3.4.2. Move and stop robot

CaoRobot::Move method moves the robot. Please refer chapter 4.2.36. for the details of Move. By adding NEXT option to Move, CaoRobot:Halt method can stop the robot motion while it is moving.

#### List 3-3

#### Robot.frm

```
Dim g_eng As CaoEngine
Dim g_ctrl As CaoController
Dim g_robot As CaoRobot

' Stop Move
Private Sub Command2_Click()
    g_robot.Halt
End Sub

' Start Move
Private Sub Command1_Click()
    g_robot.Move 1, "@P P10", "NEXT"
End Sub

Private Sub Form_Load()
    Set g_eng = New CaoEngine
    Set g_ctrl = g_eng.Workspaces(0).AddController("RC7M", "caoProv.DENSO.NetwoRC", "",
"conn=eth:10.6.235.60")
    Set g_robot = g_ctrl.AddRobot("Arm")
End Sub

Private Sub Form_Unload(Cancel As Integer)
    g_ctrl.Robots.Clear
    Set g_robot = Nothing
    g_eng.Workspaces(0).Controllers.Remove g_ctrl.Index
    Set g_ctrl = Nothing
    Set g_eng = Nothing
End Sub
```

### 3.5. Another samples

Please refer to ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Sample and its subdirectories of ORiN2 SDK for other samples.

**Table 3-1 Sample program list**

| Sample name | Division                                 | Content                                                                                                                                                                                                                                                                                                                                                          |
|-------------|------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Variable    | CaoVariable                              | Read/Write controller variable, I/O and CNF.                                                                                                                                                                                                                                                                                                                     |
| File        | CaoFile                                  | Read/Write file of controller.                                                                                                                                                                                                                                                                                                                                   |
| Tree        | CaoFile                                  | Display folder list and get file in the controller.                                                                                                                                                                                                                                                                                                              |
| Log         | CaoFile                                  | Get controller's error log and operation log.                                                                                                                                                                                                                                                                                                                    |
| Task        | CaoTask                                  | Display information and operate (start and stop) controller's task.<br>[note] The task cannot start with RC5.<br> <b>2.330</b>                                                                                                                                                |
| Robot       | CaoRobot                                 | Execute robot motion command, get robot current position, call user extension command.<br>[note] RobSlave.pac, UserExtention.pac and RobSlave.h files stored at ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Bin are necessary.<br>[note] Cannot use this with RC5.<br> <b>2.330</b> |
| Trans       | CaoController<br>CaoVariable<br>CaoFile  | Backup and restore Controller's all data.                                                                                                                                                                                                                                                                                                                        |
| Info        | CaoController<br>CaoVariable<br>CaoRobot | Display information of controller.                                                                                                                                                                                                                                                                                                                               |
| Tracking    | CaoRobot                                 | Sample code for the Conveyer Tracking function.<br>[note] Cannot use this with RC5.<br> <b>2.330</b>                                                                                                                                                                        |
| SrvLog      | CaoRobot                                 | Single axis control log acquisition.<br>[note] Cannot use Run and Motor command with RC5.<br> <b>2.330</b>                                                                                                                                                                  |

## 4. Outline of provider

### 4.1. List of method

**Table 4-1 List of method**

| Category             | Method/Property      | Function                                      |       |
|----------------------|----------------------|-----------------------------------------------|-------|
| <b>caoWorkspace</b>  |                      |                                               |       |
|                      | Addcontroller        | Connects communication to RC.                 | P. 34 |
| <b>caoController</b> |                      |                                               |       |
|                      | AddCommand           |                                               | P. 36 |
|                      | AddFile              | Connects to file or folder(PAC, system file). | P. 36 |
|                      | AddRobot             | Connects robot.                               | P. 37 |
|                      | AddTask              | Connects task.                                | P. 38 |
|                      | AddVariable          | Connects variable.                            | P. 38 |
|                      | get_TaskNames        | Get list of tasks.                            | P. 39 |
|                      | get_VariableNames    | Get list of variables.                        | P. 39 |
|                      | Execute              | Execute command of controller.                | P. 39 |
|                      | OnMessage            | Event of OnMessage                            | P. 43 |
| <b>CaoCommand</b>    |                      |                                               |       |
|                      | Execute              | Execute command.                              | P. 44 |
|                      | get_Parameters       | Get parameter of execution.                   | P. 44 |
|                      | put_parammeters      | Set parameter of execution.                   | P. 44 |
| <b>CaoFile</b>       |                      |                                               |       |
|                      | AddFile              | Connect pac file or controller folder.        | P. 44 |
|                      | AddVariable          | Connect system variable of files.             | P. 45 |
|                      | get_VariableNames    | Get list of system variable name.             | P. 45 |
|                      | Copy                 | Copy file.                                    | P. 45 |
|                      | Delete               | Delete file.                                  | P. 45 |
|                      | Move                 | Move file.                                    | P. 45 |
|                      | get_DateCreated      | Get created date.                             | P. 45 |
|                      | get_DateLastAccessed | Get accessed date.                            | P. 45 |
|                      | get_DateLastModified | Get Modified date.                            | P. 45 |
|                      | get_FileNames        | Get list of files.                            | P. 45 |
|                      | get_Attribute        | Get attributes of file.                       | P. 45 |
|                      | get_Path             | Get path of file.                             | P. 46 |
|                      | get_Size             | Get size of file.                             | P. 46 |
|                      | get_Type             | Get extension of file.                        | P. 46 |
|                      | get_Value            | Get value of file.                            | P. 46 |
|                      | put_Value            | Set value of file.                            | P. 46 |
| <b>CaoRobot</b>      |                      |                                               |       |

|             |                   |                                                                    |       |
|-------------|-------------------|--------------------------------------------------------------------|-------|
|             | Accelerate        | Set the internal acceleration and deceleration ratio of the robot. | P. 46 |
|             | AddVariable       | Connect the system variable                                        | P. 46 |
|             | get_VariableNames | Get catalogue of the system variable.                              | P. 46 |
|             | Halt              | Stop the robot motion.                                             | P. 46 |
|             | Change            | Change the tool / user coordinate system of robot.                 | P. 47 |
|             | Drive             | This method is not supported directly in this provider.            | P. 47 |
|             | Move              | Robot moves.                                                       | P. 47 |
|             | Rotate            | Robot rotates around the specified axis.                           | P. 51 |
|             | Speed             | Set the internal movement speed of the robot.                      | P. 52 |
|             | Execute           | Execute command of robot.                                          | P. 53 |
| CaoTask     |                   |                                                                    |       |
|             | AddVariable       | Connect the system variable of the robot.                          | P. 72 |
|             | get_VariableNames | Get list of the system variable.                                   | P. 73 |
|             | Start             | Start the pac program.                                             | P. 73 |
|             | Stop              | Stop the pac program                                               | P. 73 |
| CaoVariable |                   |                                                                    |       |
|             | get_Value         | Get value.                                                         | P. 73 |
|             | put_Value         | Set value.                                                         | P. 73 |
|             | put_ID            | Set variable number.                                               | P. 73 |
|             | get_ID            | Get variable number.                                               | P. 74 |
|             | get_Microsecond   | Get Timestamp.                                                     | P. 74 |
| CaoMessage  |                   |                                                                    |       |
|             | Clear             | Clear error.                                                       | P. 74 |

## 4.2. Method and Property

#### 4.2.1. CaoWorkspace::AddController method

At AddController, NetwoRC provider refers communication connection parameters and connects communication.

Option specifies communication method, connection parameter and time-out time. Option and option are delimited by “,”.

**Syntax** AddController( <bstrCtrlName:BSTR>,<bstrProvName:BSTR>,  
<bstrPcName:BSTR >[,<bstrOption:BSTR>] )

|              |   |      |                                                       |
|--------------|---|------|-------------------------------------------------------|
| bstrCtrlName | : | [in] | Controller name                                       |
| bstrProvName | : | [in] | Provider name (Fixed to “CaoProv.DENSO.NetwoRC”)      |
| bstrPcName   | : | [in] | Provider execution machine name                       |
| bstrOption   | : | [in] | Option character string = “<option1>, <option2>, ...” |

Following is a list of option string items.

### Table 4-2 Option cstring of CaoWorkspace::AddController

| Option                                            | Explanation                                                                                                                                                                                                                                                                                                                                                                                                            |
|---------------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Conn=< connected parameter >                      | Mandatory. Communication method and connection parameters are set.<br>Refer 2.2.1.1 for details.                                                                                                                                                                                                                                                                                                                       |
| MyIP=[<local IP address>]:[local UDP port number] | Specify the IP address and UDP port number of the local machine.<br><br>In case of multiple NICs, MyIP option is used to specify a NIC. If this option was omitted, the first NIC is selected automatically. If an invalid IP was set, an error occurs.<br><br>If the UDP port number is not specified, the system assigns an appropriate port number automatically.<br><br>In case of RS232c, this option is ignored. |
| Timeout=< Time-out time >                         | Communication time-out time. (default: 400) msec                                                                                                                                                                                                                                                                                                                                                                       |
| TORetry=<Retry count>                             | Communication retry count. 1 – 7 (default:5)<br><br>It is treated as 1 in case of 1 or less.<br><br>It is treated as 7 in case of 7 or more.                                                                                                                                                                                                                                                                           |
| CtrlChk=True/False                                | Connection check. (default: False)                                                                                                                                                                                                                                                                                                                                                                                     |

In case of RS232C, only one CaoController object is creatable for one RS232C port.

#### 4.2.1.1. Conn option

Following is communication parameter string for Comm option. Square blanket (“[]”) means the parameter can be omitted. Underline part shows the default value when the option is not specified.

##### • RS232C device

“com:[<COM Port>[:<BaudRate>[:<Parity>:<DataBits>:<StopBits>]]]”

<COM Port> : COM port number. ‘1’-COM1, ‘2’-COM2,...

<BaudRate> : Transmission rate. 4800,9600,19200,38400,57600,115200.

<Parity> : Parity. ‘N’-NONE, ‘E’-EVEN, ‘O’-ODD.

<DataBits> : Number of data bits. ‘7’-7bit, 8’-8bit.

<StopBits> : Number of stop bits. ‘1’-1bit, ‘2’-2bit.

##### • EtherNet device

“eth:<IP Address>[:<Port No>]”

<IP Address> : Internet Protocol address.

Example: "127.0.0.1", "192.168.0.1"

<Port No> : UDP connection port number. 4112, 4113... any port number can be assigned.

#### 4.2.2. CaoController::AddCommand method

The argument of the AddCommand method of the CaoController class specifies the command name (BSTR type).

#### 4.2.3. CaoController::AddFile method

The argument of the AddFile method of the CaoController class specifies the file name (BSTR type). The specified "File name" is PAC program name or the system reserved file name.

An directory can be specified as an argument by designating only file path. If the path is not specified, files in the default directory "/rom/prj" are specified.

Following shows the argument specification of AddFile.

**Syntax** AddFile( <bstrName:BSTR > [, <bstrOption:BSTR>] )

bstrName : [in] File name

bstrOption : [in] Option character string

The option uses the following character strings.

**Table 4-3 Option character string of CaoController::AddFile**

| Option             | Meaning                                                                                                                                                                                                                                                                       |
|--------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| @Create[=<0 to 2>] | When the specified file does not exist, the file is created according to this option.<br>0:The file is not created. (default)<br>1:The file is made.<br>2:The directory is made.<br>If the specified file exists, or the file name is the drive name, this option is ignored. |

The table below shows the list of the file. Please refer to the file specification for a detailed format of the file.

**Table 4-4 File implementation status list**

|   | ORiN2 file name | Form | Explanation      |
|---|-----------------|------|------------------|
| 1 | *.PAC           | text | PAC source       |
| 2 | *.H             | text | PAC header       |
| 3 | *.NIC           | bin  | PAC execute form |

|    |                |      |                                           |
|----|----------------|------|-------------------------------------------|
| 4  | *.MAP          | text | Refer between PAC.                        |
| 5  | @VAR_INT       | bin  | I type variable                           |
| 6  | @VAR_SNG       | bin  | F type variable                           |
| 7  | @VAR_DBL       | bin  | D type variable                           |
| 8  | @VAR_VEC       | bin  | V type variable                           |
| 9  | @VAR_POS       | bin  | P type variable                           |
| 10 | @VAR_JNT       | bin  | J type variable                           |
| 11 | @VAR_TRN       | bin  | T type variable                           |
| 12 | @VAR_STR       | bin  | S type variable                           |
| 13 | @VAR_TOOL      | bin  | Tool coordinates definition               |
| 14 | @VAR_WORK      | bin  | Work coordinates definition               |
| 15 | @VAR_AREA      | bin  | Area definition                           |
| 16 | @LOG_ERROR     | bin  | Error log                                 |
| 17 | @LOG_OPERATION | bin  | Operation log                             |
| 18 | @LOG_CONTROL   | bin  | Control log                               |
| 19 | @CNF_ITP       | bin  | Interpreter environment setting           |
| 20 | @CNF_PAC       | bin  | Program environment setting               |
| 21 | @CNF_DIO       | bin  | I/O environment setting                   |
| 22 | @CNF_ARM       | bin  | Trajectory generation environment setting |
| 23 | @CNF_SRV       | bin  | Servo environment setting                 |
| 24 | @CNF_SPD       | bin  | Usage condition setting                   |
| 25 | @CNF_VIS       | bin  | Vision environment setting                |
| 26 | @CNF_COM       | bin  | Communication environment setting         |

### 【 attention 】

CaoFile object does not support simultaneous access to a file.

Be sure to implement exclusive file access control routine in the application.

#### 4.2.4. CaoController::AddRobot method

The argument of the AddRobot method of the CaoController class specifies the robot name (BSTR type). “Robot name” specified here is an arbitrary string. For instance, specify like AddRobot(“ROBOTalk1”). A CaoRobot object is retrieved by calling the AddRobot method.

**Syntax** AddRobot( <bstrName:BSTR > [,<bstrOption:BSTR>] )

bstrName : [in] Robot name

bstrOption : [in] Option character string (unused)

#### 4.2.5. CaoController::AddTask method

The argument of the AddTask method of the CaoController class specifies the task name (BSTR type). “Task name” specified here specifies a PAC program name. For instance, the CaoTask object is retrieved in the expression like AddTask(“pro1”).

**Syntax** AddTask( <bstrName:BSTR> [, <bstrOption:BSTR>] )

bstrName : [in] Task name  
bstrOption : [in] Option character string (unused)

If “@ALL” is specified as a task name, a created CaoTask object provides CaoTask::Start method and CaoTask::Stop method for the all tasks.

#### 4.2.6. CaoController::AddVariable method

The AddVariable method of this CaoController class is a method for the access to the variable. In the NetwoRC provider, both the user variable and the system variable can be specified for the variable name.

User variable supports following variables, i.e., controller variable (I,F,V,P,J,D,T,S), I/O, and system parameter (CNF). Following is the argument specification of AddVariable.

**Syntax** AddVariable( <bstrName:BSTR> [, <bstrOption:BSTR>] )

bstrName : [in] Variable name  
bstrOption : [in] Option character string

<Variable identifier> : I, F, V, P, J, D, T, S, IO, TOOL, WORK, AREA, \_ ITP, \_ PAC, \_ DIO, \_ ARM, \_ SRV, \_ SPD, \_ VIS, \_ COM, WDIIn, WDOOut  
The character is not case-sensitive (uppercase and lowercase has same meaning).  
System variable (CNF) begins with “\_” (underscore).  
< number > : Variable index or ‘\*’ or ‘\*\_<Index>’  
The number is specified by a decimal number.  
In case of ‘\*’, the initial index is 0. The index can be retrieved and changed by ‘ID’ property.  
< option > : “LEN=<bit length>” (valid only for I/O variables)  
<bit length>: 1 or 8 or 16. (default = 1)

“[” and ”]” can be omitted.

|             |                    |     |                                                |
|-------------|--------------------|-----|------------------------------------------------|
| (example 1) | “i0”, “I[0]”       | ... | specify the 0 <sup>th</sup> I type variables.  |
| (example 2) | “IO128”, “io[128]” | ... | specify the 128 <sup>th</sup> I/O variables.   |
| (example 3) | “_ARM0”, “_arm[0]” | ... | specify the 0 <sup>th</sup> element of ARMCNF. |

(The number of elements of ???CNF is stored

in ???CNF[0]. )

(example 4) “\_itp19”, “\_itp[19]” ... specify the 19<sup>th</sup> element of ITPCNF.

(example 5) “tool10”, “tool[10]” ... specify the 10<sup>th</sup> element of Tool.

(example 6) “I\*”, “\_PAC[\*]” ... specify the index by ID property.

(example 7) “I\*\_1”, “I\*\_2”, “I\*\_3” ... create various I\*

Please note that the number of CNF variable (\_ITP,\_PAC,\_DIO,\_ARM,\_SRV,\_SPD,\_VIS,\_COM) is not as same as the number displayed on NetwoRC teach pendant. The value shifts because the 0<sup>th</sup> number of elements is not displayed in the pendant. (in many cases, CNF variable = pendant display +1)

When a system variable is specified, “@” is applied at the beginning of the variable name. All variable names without “@” at the beginning is treated as an user variable.

Please refer 4.3Variable list about the system variable implemented in the NetwoRC provider.

#### 4.2.7. CaoController::get\_TaskNames property<sup>5</sup>

A list of the PAC program name that can be specified by the AddTask method is acquired.

#### 4.2.8. CaoController::get\_VariableNames property

A list of the variable identifier and the system variable identifier that can be specified by the AddVariable method is acquired.

#### 4.2.9. CaoController::Execute method

The argument of the Execute method of the CaoController class specifies the command name (BSTR type).

The list of the command that can be specified is shown in Table 4-5.

**Syntax** [<vntRet:VARIANT> = ] Execute( <bstrCmd:BSTR> [,<vntParam:VARIANT>] )

|          |   |       |              |
|----------|---|-------|--------------|
| bstrCmd  | : | [in]  | Command      |
| vntParam | : | [in]  | Parameter    |
| vntRet   | : | [out] | Return value |

#### Example

```
Dim vRes as Variant
vRes = caoCtrl.Execute("GetAutoMode")
```

<sup>5</sup> = VT\_ARRAY|VT\_VARIANT (less than Ver1.1.0, VT\_ARRAY|VT\_BSTR)

**Table 4-5 CaoController::Execute method implemented command list**

| Command                    | Parameter                                                                                                                                                         | Return value                                                                                                                                                           | Operation              |
|----------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------|
| GetAutoMode                | None                                                                                                                                                              | <Mode:VT_I2> =<br>0:Unkown<br>1:Internal auto<br>2:External auto                                                                                                       | Get auto mode          |
| PutAutoMode                | <Mode:VT_I2> =<br>1:Internal auto<br>2:External auto                                                                                                              | None                                                                                                                                                                   | Set auto mode          |
| StartLog                   | None                                                                                                                                                              | None                                                                                                                                                                   | Start log recording    |
| StopLog                    | None                                                                                                                                                              | None                                                                                                                                                                   | Stop log recording     |
| ClearLog                   | None                                                                                                                                                              | None                                                                                                                                                                   | Clear log data         |
| SaveFile                   | None                                                                                                                                                              | None                                                                                                                                                                   | Request to save file   |
| GetFileTransMode           | None                                                                                                                                                              | <Mode :VT_I4> :=<br>File transfer mode<br>0= normal transfer<br>0bit: Old procedure<br>1bit: ROM operation<br>2bit: Status notification<br>(with OnMessage<br>event. ) | Get file transfer mode |
| PutFileTransMode<br><Mode> | <Mode :VT_I4> =<br>File transfer mode<br>0=normal transfer<br>0bit: Old procedure<br>1bit: ROM operation<br>2bit: Status notification<br>(With OnMessage event. ) | None                                                                                                                                                                   | Set file transfer mode |

|                                            |                                                                                                                                                                          |                                      |                                                                                                                                   |
|--------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------|--------------------------------------|-----------------------------------------------------------------------------------------------------------------------------------|
| ChangeConfig<br><CnfID>                    | <CnfID:VT_I2> =<br>1 : COMCNF<br>2 : ARMCNF<br>3 : VISCNF<br>4 : PACCNF<br>5 : SRVCNF<br>6 : SPDCNF<br>7 : ITPCNF<br>8 : DIOCNF<br>9 : SYSCNF                            | None                                 | Change notice of CNF                                                                                                              |
| SetDummyIO<br><IO><br><Value><br>[<Range>] | <IO:VT_I2> =<br>I/O number<br><Value:VT_I2> =<br>State 0: OFF 1:ON<br>[<Range:VT_I2>] =<br>Range(default: 1. )<br>ex. 1 -> Only < IO ><br>8 -> From < IO ><br>To < IO>+7 | None                                 | Set pseudo input<br>All setting is cleared<br>when < IO>=-1<br>(<Value> is ignored.<br>Range must be omitted<br>or specify 1 )    |
| GetDummyIO<br><IO><br><Value>              | <IO:VT_I2> =<br>I/O number                                                                                                                                               | <Value:VT_I2> =<br>State 0: OFF 1:ON | Get pseudo input                                                                                                                  |
| LoadNIC<br><WaitForCompletion>             | < WaitForCompletion :VT_BOOL> =<br>Wait load completion.<br>(True/False)                                                                                                 | None                                 | Load NIC file.                                                                                                                    |
| DoSignal<br><Mode><br><Action>             | < Mode :VT_I4>= mode<br>< Action :VT_I4>= action                                                                                                                         | None                                 | Notify the timing of<br>process start to<br>controller                                                                            |
| GetVarSize<br><Type>                       | <Type of variable:VT_BSTR><br>"I","F","D","V","P","J","T","S"                                                                                                            | <Size:VT_I4>                         | Get the variable<br>number.                                                                                                       |
| Compile                                    | None                                                                                                                                                                     | None                                 | Execute the<br>compilation.<br> <b>2.330</b> |

|                                 |                                                |                                                                                                                                                                                                   |                                                                                                                                                    |
|---------------------------------|------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------|
| GetCompileState                 | None                                           | <Mode:VT_I4> :=<br>1 : Compiling. ( or<br>Loading)<br>0: Normal termination<br>-1 : Abnormal<br>termination ( Compile<br>error)<br>-2 : Abnormal<br>termination ( Excluding<br>the compile error) | Get the progress report<br>of the compilation.<br> <b>2.330</b> |
| SetExtension                    | <Mode:VT_I2>=<br>1:Add,2:Remove<br><Key:VT_I4> | None                                                                                                                                                                                              | Add or remove robot<br>controller extension.                                                                                                       |
| ClearError                      | <Error No.:VT_I4>                              | <Res:VT_I2>=<br>0:OK, -1:NG                                                                                                                                                                       | Clear robot controller<br>error.                                                                                                                   |
| InitNonStopPathLib <sup>6</sup> | None                                           | None                                                                                                                                                                                              | Initializate non-stop<br>trajectory generation<br>process                                                                                          |

<sup>6</sup> 【Attention】Additional license for "Non-Stop Motion Calculator" is required to use this Command.

|                                  |                                                                                                                                                                                                                                                                                                                                                |                                           |                                                                                                                                                                                                                                                                  |
|----------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|-------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| GenerateNonStopPath <sup>7</sup> | <Teaching Points: <Position>   VT_ARRAY>,<br><Area: <Area>   VT_ARRAY>,<br><Teaching Point Number: VT_I4>,<br><Total speed rate: VT_R4(0.0~1.0)>,<br><Convergence Coefficient: VT_R4(0.0~1.0)>,<br>[<Adjustment Method: VT_I4> = 1 :<br>Synchronous motion with<br>Extended-Joint(default), 0 :<br>Asynchronous motion with<br>Extended-Joint] | <Motion Points:<br><Position>   VT_ARRAY> | Generate non-stop trajectory.<br><br>The first <Teaching Point> is Start Point, and the Last point is End Point.<br><br>For detailed information, refer to “6.1.3.Appendix F.Non-Stop Motion Calculator - Trajectory Generator Command for Non Stop Inspection ” |
|----------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|-------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|

#### 4.2.10. CaoController::OnMessage event

The table below shows the implemented OnMessage event of the CaoController class.

**Table 4-6 OnMessage event implementation list**

| Number | Data type | Content of notification | Meaning                                                                                                                                                     |
|--------|-----------|-------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------|
| 1      | VT_BSTR   | Error message           | The error occurs.                                                                                                                                           |
| 2      | VT_BSTR   | Error message           | There is no response.                                                                                                                                       |
| 3      | VT_I4     | <LONG:RangeMax>         | GetText: Start<br>Progress status notification starts. Maximun range is <RangeMax>.<br>The bit2 of Execute(“Put_FileTransMode <Mode>”) need to be set as 1. |
| 4      | VT_I4     | <LONG:Range>            | GetText: Progressing and returns status.<br>The bit2 of Execute(“Put_FileTransMode <Mode>”) need to be set as 1.                                            |

<sup>7</sup> 【Attention】Additional license for "Non-Stop Motion Calculator" is required to use this Command.

|   |       |                                   |                                                                                                                                                                |
|---|-------|-----------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------|
| 5 | VT_I4 | < LONG:RangeMax ><br>or -1(error) | GetText: Completed. Returns maximum range size if normally finished. Returns -1 if NG.<br>The bit2 of Execute("Put_FileTransMode <Mode>") need to be set as 1. |
| 6 | VT_I4 | <LONG:RangeMax>                   | PutText: Start<br>Progress status notification starts. Maximun range is <RangeMax>.<br>The bit2 of Execute("Put_FileTransMode <Mode>") need to be set as 1.    |
| 7 | VT_I4 | <LONG:Range>                      | PutText: Progressing and returns status.<br>The bit2 of Execute("Put_FileTransMode <Mode>") need to be set as 1.                                               |
| 8 | VT_I4 | <LONG:RangeMax> or<br>-1(error)   | PutText: Completed. Returns maximum range size if normally finished. Returns -1 if NG.<br>The bit2 of Execute("Put_FileTransMode <Mode>") need to be set as 1. |

#### 4.2.11. CaoCommand::Execute method

A command is executed.

Please refer to Table 4-5 for necessary parameters for command execution and returned result.

Parameters necessary to execute command need to be specified by PutParameters property beforehand.

#### 4.2.12. CaoCommand::get\_Parameters property

Get currently set execution parameters.

#### 4.2.13. CaoCommand::put\_Parameters property

Set command execution parameters.

Required parameters differ depending on the command to be executed. Please refer Table 4-5 for command name and parameters to be set.

Even if the content of the parameter doesn't match the specification of executed command, this property doesn't return an error. The error is returned when the command is executed.

#### 4.2.14. CaoFile::AddFile method

Create an file object like in the same way as 4.2.3. The file path corresponding to the created CaoFile object is "<path of the parent object>/<fine name specified in AddFile>".

**4.2.15. CaoFile::AddVariable method**

The argument of the AddVariable method of the CaoFile class specifies the system variable name.

Please refer Table 4-14 for the list of implemented system variables.

**4.2.16. CaoFile::get\_VariableNames property**

A list of the variable identifier and the system variable identifier that can be specified by the AddVariable method is acquired.

**4.2.17. CaoFile::Copy method**

Copy a file corresponding to the object to the specified place.

**4.2.18. CaoFile::Delete method**

Delete a file corresponding to the object. After the deletion of the file, object is not deleted. If the object is not necessary, client program need to delete the object.

**4.2.19. CaoFile::Move method**

Move a file corresponding to the object. The placement of the corresponding file is changed, but object name is not changed.

**4.2.20. CaoFile::get\_DateCreated property**

Get the file creation date of the file corresponding to the object.

**4.2.21. CaoFile::get\_DateLastAccessed property**

Get the last file access date of the file corresponding to the object.

**4.2.22. CaoFile::get\_DateLastModified property**

Get the last file modification date of the file corresponding to the object.

**4.2.23. CaoFile::get\_FileNames property <sup>8</sup>**

Get a list of file in the directory.

Only executable when the path corresponding to the object is a directory.

**4.2.24. CaoFile::get\_Attribute property**

Get the attribute of the file corresponding to the object.

---

<sup>8</sup> = VT\_ARRAY|VT\_VARIANT (less than Ver1.1.0, VT\_ARRAY|VT\_BSTR)

**4.2.25. CaoFile::get\_Path property**

Get the path to the file corresponding to the object. The retrieved value does not include file name.

**4.2.26. CaoFile::get\_Size property**

Get the size of the file corresponding to the object.

**4.2.27. CaoFile::get\_Type property**

Get the extension of the file corresponding to the object.

**4.2.28. CaoFile::get\_Value property**

Get the contents of the file corresponding to the object.

**4.2.29. CaoFile::put\_Value property**

Set the contents of the file corresponding to the object.

**4.2.30. CaoRobot::Accelerate method**

Set the internal acceleration and deceleration ratio of the robot.

This method corresponds to ACCEL instruction of PAC language.

Following is the argument specifications of Accelerate.

**Syntax** Accelerate <lAxis:LONG >, <fAccel:FLOAT> [,<fDecel:FLOAT>]

lAxis : [in] Axis number -1: Tool accel (ACCEL), 0: All axes (JACCEL)

fAccel : [in] Acceleration (-1: keep current setting)

fDecel : [in] Deceleration (-1: keep current setting)

Example 1. Accelerate 0, 50.0, -1 // acceleration =50%, deceleration = no change.

Example 2 Accelerate 0, -1, 60.0 // acceleration = no change, deceleration =60%

**4.2.31. CaoRobot::AddVariable method**

The argument of the AddVariable method of the CaoRobot class specifies the system variable name.

The list of the implemented system variable is shown on Table 4-12.

**4.2.32. CaoRobot::get\_VariableNames property**

A list of the variable identifier and the system variable identifier that can be specified by the AddVariable method is acquired.

**4.2.33. CaoRobot::Halt method**

By adding “NEXT” option to a CaoRobot class motion method like Move, Drive or Rotate, the motion

method are executed asynchronously. While a robot moves with an asynchronously executed motion method, Halt method can stop the robot motion.

However, if two or more asynchronous motion methods are executed in succession, halt method cannot stop robot motion. In this case, before the preceding motion method execution is finished, next motion method goes into “wait” status. In this status, OnMessage event of CaoController class is periodically issued, and Halt method is not accepted. To stop robot motion in this status, one of following action is necessary.

- (6) Stop the execution of “ROBSLAVE” task using Stop method of CaoTask class
- (7) Input robot stop signal from dedicated I/O port.

Executing Halt method while robot is not moving has no effect on robot motion.

#### 4.2.34. CaoRobot::Change method



Change the tool / user coordinate system of robot.

This method corresponds to CHANGETOOL and the CHANGEWORK instruction of PAC language.

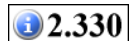
Following is the argument specifications of Change method.

**Syntax** Change <bstrName:BSTR>

bstrName : [in] for CHANETOOL= “Tool <number>”  
for CHANGEWORK= “Work <number>”

<number> : numerical value expressed by decimal number

#### 4.2.35. CaoRobot::Drive method



This method is not supported directly in this provider.

Instead, please use “DriveEx” or “DriveAEx” command of CaoRobot::Execute that can operate two or more axes all at once.

#### 4.2.36. CaoRobot::Move method



Robot moves to the specified coordinates.

This method corresponds to MOVE instruction PAC language.

Following is the Move argument specifications.

**Syntax** Move <lComp:LONG >, <vntPose:POSEDATA>, <bstrOpt:BSTR>

lComp : [in] Interpolation 1:MOVE P,... , 2:MOVE L,... , 3:MOVE C,... , 4:MOVE S,...  
vntPose [in] Pose data  
bstrOpt [in] Motion option, “NEXT” =Asynchronous call

Please refer to “6.1.3.Appendix APOSEDATA type definition” for the POSEDATA type..

The form and the meaning when the character string is specified by the POSEDATA type are as follows.

**In case of VT\_BSTR**

- If Comp = 1, 2

“[<@pass motion beginning displacement>] <pose> [<extended-joints>]”

ex. “P1”, “@P T100”, “@E J520”

- If Comp = 3

“<pose 1> [<extended-joints>], [<@ pass motion beginning displacement>] <pose 2> [<extended-joints>]”

- \*\*\* pose 1 and pose 2 need to be same variable type. \*\*\*

ex. “P1, @E P2”, “T100, @P T101”

- If Comp = 4

“[<@pass motion beginning displacement>] <free curve trajectory number> [<extended-joints>]”

ex. “1”, “@P 20”, “@E 5”

<free curve trajectory : a decimal number (1 to 20)  
number>

<pose> : “<variable type><variable number>” or

“[<variable type>](<element1>,<element2>,...)”

: <variable type> : One character either ‘P’, ‘T’ or ‘J’

<variable number> : a decimal number

<element n> : an element of variable either ‘P’, ‘T’ or ‘J’

P(<x>,<y>,<z>,<rx>,<ry>,<rz>,<fig>)

J(<j1>,<j2>,<j3>,<j4>,<j5>,<j6>,<j7>,<j8>)

T(<x>,<y>,<z>,<ox>,<oy>,<oz>,<ax>,<ay>,<az>,<fig>)

[Note] For 4-axis robot, T element of P type variable corresponds to  
<rz>. <rx> and <ry> are not used.

<@pass motion : “@0”, “@P”, “@E”, or “@<value>”

beginning

displacement>

<extended-joints> : The syntax of an extended-joints option is shown below.<sup>9</sup>

(Please specify the extended-joints option after the pose data and

<sup>9</sup> To use extended joint option, please define extended joint related settings (e.g. arm group definition) on the controller, and use TakeArm command to select arm group for controlled extended joint.

blank.)

“EX((<JointNumber1>, <RelativeDistance1>)[, (<JointNumber2>, <RelativeDistance2>)...])”

or

“EXA((<JointNumber1>, <AxisCoordinates1>)[, (<JointNumber2>, <AxisCoordinates2>)...])”

|            |                                                       |                                                      |
|------------|-------------------------------------------------------|------------------------------------------------------|
| Example 1. | Move 1, “@P P1” ,”NEXT”                               | ‘ MOVE P, @P P1, NEXT                                |
| Example 2  | Move 3, “P1,@E P2”                                    | ‘ MOVE C, P1,@E P2                                   |
| Example 3  | Move 2, “@0 P(307.1856,-157.8244,107.0714,160,0,0,1)” | ‘ MOVE L,@0 P(307.1856,-157.8244,107.0714,160,0,0,1) |
| Example 4  | Move 4, “@E 2”                                        | ‘ MOVE S, @E 2                                       |
| Example 5  | Move 1, “@P P10 EX((7, 30.5))” ,”NEXT”                | ‘ MOVE P, @P P10 EX((7,30.5)), NEXT                  |
| Example 6  | Move 2, “@E P20 EXA((7, 30.8), (8, 90.5))”            | ‘ MOVE L, @E P20 EXA((7, 30.8), (8, 90.5))”          |

If <NEXT option> is added, the robot proceeds to the next no-movement instruction without waiting for movement to finish.

When two or more Move method is executed consecutively, the latter motion method is in “wait” status until the preceding motion method execution ends, and application seems to be not responding. In this wait state, OnMessage event #9 of CaoController class is periodically issued, so catch the event and pass the program control to application program if necessary.

The following table shows the PAC MOVE command supported by Move method.

**Table 4-7 Move command list**

| Division   | PAC command      | Move method        |
|------------|------------------|--------------------|
| MOVE P,... | MOVE P, P<n1>    | Move 1, “P<n1>”    |
|            | MOVE P, @P P<n1> | Move 1, “@P P<n1>” |
|            | MOVE P, @E P<n1> | Move 1, “@E P<n1>” |
|            | MOVE P, T<n1>    | Move 1, “T<n1>”    |
|            | MOVE P, @P T<n1> | Move 1, “@P T<n1>” |
|            | MOVE P, @E T<n1> | Move 1, “@E T<n1>” |
|            | MOVE P, J<n1>    | Move 1, “J<n1>”    |

|                 |                                                                                                                                                                                                                                        |                                                                                                                                                                                                                                                          |
|-----------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
|                 | MOVE P, @P J<n1><br>MOVE P, @E J<n1>                                                                                                                                                                                                   | Move 1, "@P J<n1>"<br>Move 1, "@E J<n1>"                                                                                                                                                                                                                 |
| MOVE L,...      | MOVE L, P<n1><br>MOVE L, @P P<n1><br>MOVE L, @E P<n1><br>MOVE L, T<n1><br>MOVE L, @P T<n1><br>MOVE L, @E T<n1><br>MOVE L, J<n1><br>MOVE L, @P J<n1><br>MOVE L, @E J<n1>                                                                | Move 2, "P<n1>"<br>Move 2, "@P P<n1>"<br>Move 2, "@E P<n1>"<br>Move 2, "T<n1>"<br>Move 2, "@P T<n1>"<br>Move 2, "@E T<n1>"<br>Move 2, "J<n1>"<br>Move 2, "@P J<n1>"<br>Move 2, "@E J<n1>"                                                                |
| MOVE C,...      | MOVE C, P<n1>, P<n2><br>MOVE C, P<n1>, @P P<n2><br>MOVE C, P<n1>, @E P<n2><br>MOVE C, T<n1>, T<n2><br>MOVE C, T<n1>, @P T<n2><br>MOVE C, T<n1>, @E T<n2><br>MOVE C, J<n1>, J<n2><br>MOVE C, J<n1>, @P J<n2><br>MOVE C, J<n1>, @E J<n2> | Move 3, "P<n1>, P<n2>"<br>Move 3, "P<n1>, @P P<n2>"<br>Move 3, "P<n1>, @E P<n2>"<br>Move 3, "T<n1>, T<n2>"<br>Move 3, "T<n1>, @P T<n2>"<br>Move 3, "T<n1>, @E T<n2>"<br>Move 3, "J<n1>, J<n2>"<br>Move 3, "J<n1>, @P J<n2>"<br>Move 3, "J<n1>, @E J<n2>" |
| MOVE S,...      | MOVE S, n1<br>MOVE S, @P n1<br>MOVE S, @E n1                                                                                                                                                                                           | Move 4, "n1"<br>Move 4, "@P n1"<br>Move 4, "@E n1"                                                                                                                                                                                                       |
| Extended-joints | MOVE P, P<n1> EX((j1, v1))<br>MOVE P, P<n1> EX((j1, v1),(j2, v2))<br>MOVE P, P<n1> EXA((j1, v1))<br>MOVE P, P<n1> EXA((j1, v1),(j2, v2))                                                                                               | Move 1, "P<n1> EX((j1,v1))"<br>Move 1, "P<n1> EX((j1,v1),(j2, v2))"<br>Move 1, "P<n1> EXA((j1,v1))"<br>Move 1, "P<n1> EXA((j1,v1),(j2, v2))"                                                                                                             |
| Misc.           | MOVE P, P<n1> + (x,y,z,rx,ry,rz)<br>MOVE P, P<n1> + (x,y,z,rx,ry,rz)H                                                                                                                                                                  | Move 1, DEV("P<n1>", "P(x,y,z,rx,ry,rz)")<br>Move 1, DEVH("P<n1>", "P(x,y,z,rx,ry,rz)")<br><u>*Please refer to CaoRobot::Execute for DEV and DEVH.</u>                                                                                                   |

&lt; n1 &gt; ,&lt; n2&gt;: integer 0-65535

Please refer to the sample of CAO robot class robot motion command coding supplied with ORiN2 SDK, which is stored at ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Sample¥Robot.

### 【 essential requisites 】

At the current implementation, “RobSlave.pac” program need to be executed beforehand on the robot controller to execute robot motion command of CaoRobot class (Table 4-8). RobSlave.pac is in ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Bin.

Robot controller’s T[0], T[1], and I[0] variable are used for the communication. DO NOT use these variables for other purposes.

**Table 4-8 Motion Commands requiring “RobSlave.pac”**

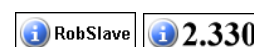
| Method                    | Command name                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                    |
|---------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| CcaoProvRobot::Accelerate |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Change     |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Halt       |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Move       |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Rotate     |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Speed      |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
| CcaoProvRobot::Execute    | Approach, Depart, Draw, Motor, ClrSplinePoint, SetSplinePoint, GetSplinePoint, WaitSplinePoint, WaitMotionEnd, MotionSkip, MotionComp, DefTool, DefWork, DefArea, Interrupt, PosClr, Arrive, RotateH, DriveEx, DriveAEx, Delay, SYSSTATE, J2P, J2T, P2J, P2T, T2J, T2P, TINV, NORMTRN, TMUL, DEV, DEVH, FIGAPRP, FIGAPRL, TrackDataInitialize, TrackDataSet, TrackDataGet, TrackDataInfo, TrackDataNum, CurTrackPos, CurTrackSpd, WaitTrackMove, CalcWorkPos, CurTrackPosEx, WaitTrackMoveEx, SetTrackMove, ResetTrackMove, SetTrackStartArea, UserExt, ST_*, TakeArm, GiveArm, |

**【 attention 】**

All global variables (I, F, D, V, P, J, T, S) from [0] to [9] have been reserved with the system.

Please do not access these variables in the user’s program.

#### 4.2.37. CaoRobot::Rotate method



Robot rotates around the specified axis.

This method corresponds to ROTATE instruction PAC language.

Following is the Rotate argument specifications.

**Syntax** Rotate <vntRotSuf:POSEDATA>, <fDeg:FLOAT>, <vntPivot:POSEDATA>, <bsreOpt:BSTR>

|           |   |      |                                             |
|-----------|---|------|---------------------------------------------|
| vntRotSuf | : | [in] | rotation surface                            |
| fDeg      | : | [in] | angle(deg)                                  |
| vntPivot  | : | [in] | rotation center                             |
| bsrOpt    | : | [in] | motion option                               |
|           |   |      | motion option, “@0”, “@P”, “@E”, “@<value>” |
|           |   |      | or “pose=<n>”                               |
|           |   |      | or “NEXT”                                   |

Please refer to “6.1.3.Appendix APOSEDATA type definition” for the POSEDATA type..

The form and the meaning when the character string is specified by the POSEDATA type are as follows.

#### In case of VT\_BSTR

- vntRotSuf: [in] rotation surface  
 “V <n1>, V <n2>, V <n3>” or “XY”, “YZ”, “ZX”, “XYH”, “YZH”, “ZXH”  
 or “V(<x>,<y>,<z>),V(...),V(...)”  
 ex. “V100,V101,V102”
- vntPivot: [in] rotation center  
 “V <n4>” or “V(<x>,<y>,<z>)”  
 ex. “V103”

Example 1. Rotate “V1,V2,V3”, 45.8, “V4”, “@E”      ‘ ROTATE V1,V2,V3, @E 45.8, V4

Example 2. Rotate “V(0,0,1),V(0,1,0),V(0,0,0)”, 30.0, “V(0,0,0)”, “@E,pose=1,NEXT”

Example 3. Rotate “XY”, 90.0, “V(0,0,0)”, “@P”

Example 4. Rotate “XYH”, -45.0, “V(250,0,0)”, “@150”

Rotation surface is specified by three V type variables. The three points in base coordinate system defines the surfaces. Argument vntRotSuf specifies three V type variables in BSTR (string) type variable separated by comma, space or tab.

Rotation center point vntPivot is specified by a V type variable expressed in BSTR(string) type.

#### 4.2.38. CaoRobot::Speed method



The internal movement speed of the robot is specified.

This method corresponds to SPEED and JSPEED instruction PAC language.

About the external movement speed of the robot, please use “ExtSpeed” command of CaoRobot::Execute.

Following is the Speed argument specifications

**Syntax** Speed <lAxis:LONG >, <fSpeed:FLOAT>

lAxis : [in] axis number  
-1:effective to Tool axis(SPEED), 0:effective to all axis(JSPEED)

fSpeed : [in] speed

#### 4.2.39. CaoRobot::Execute method



The Execute method defines peculiar operation commands to the robot that isn't supported by the CaoRobot class, and offers the function to implement them.

**Syntax** [<vntRet:VARIANT> = ] Execute( <bstrCmd:BSTR > [,<vntParam:VARIANT>] )

bstrCmd : [in] Command

vntParam : [in] Parameter

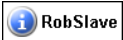
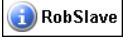
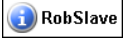
vntRet : [out] Return value

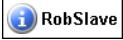
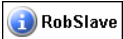
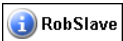
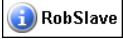
The list shows available commands.

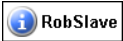
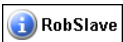
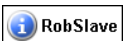
**Table 4-9 List of implemented Execute command of CaoRobot class<sup>10</sup>**

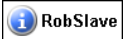
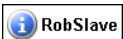
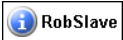
| Command    | Parameter                                          | Return value     | PAC command                                                         |
|------------|----------------------------------------------------|------------------|---------------------------------------------------------------------|
| UserExt    | <command number:VT_I4> ,<br><parameter 1:VT_R4>... | VT_R4   VT_ARRAY | Execute extension method.                                           |
| GetJntData | <data number:VT_I4>,<axis<br>number:VT_I2>         | VT_R4            | GetJntData<br>Gets the internal servo data<br>of a specified joint. |
| GetSrvData | <data number:VT_I4>                                | VT_R4   VT_ARRAY | GetSrvData<br>Gets the internal servo data<br>of robot joints.      |

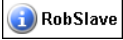
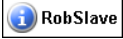
<sup>10</sup> Please refer to "6.1.3.Appendix APOSEDATA type definition" for the POSEDATA type.

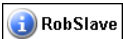
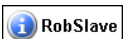
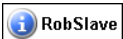
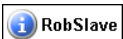
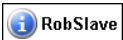
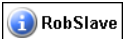
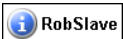
|                |                                                                                                                                                                                          |                                        |                                                                                                                                                                                                                                                                                                                       |
|----------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------------------------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Approach       | <p>&lt; Interpolation method:VT_I2 (=1:P, 2:L) &gt;</p> <p>&lt; base variable :POSEDATA-C0&gt;</p> <p>&lt; [pass] approach length : POSEDATA-C2&gt;</p> <p>[,option :VT_BSTR "NEXT"]</p> | None                                   | <p>APPROACH &lt;Interpolation method&gt;, &lt;pose variable type&gt;&lt;pose variable number&gt;, &lt;pass&gt; &lt;approach length&gt;[, NEXT]</p> <p>Execute the absolute movement designated in the tool coordinate system.</p>  |
| Depart         | <p>&lt; Interpolation method:VT_I2 (=1:P, 2:L) &gt;</p> <p>&lt; [pass] approach length : POSEDATA-C2 &gt;</p> <p>[,option :VT_BSTR "NEXT"]</p>                                           | None                                   | <p>DEPART &lt;Interpolation method&gt;, &lt;pass&gt; &lt;approach length&gt;[, NEXT]</p> <p>Executes the relative motion in the tool coordinate system.</p>                                                                      |
| ExtSpeed       | <p>&lt;external speed:VT_R4 (=0.1 to 100.0)&gt; ,</p> <p>&lt;external acceleration:VT_R4 (=0.0001 to 100.0)&gt; ,</p> <p>&lt; external deceleration:VT_R4 (=0.0001 to 100.0)&gt;</p>     | None                                   | <p>ExtSpeed,ExtAcc,ExtDec</p> <p>Sets the external speed.</p>                                                                                                                                                                                                                                                         |
| SetSplinePoint | <p>&lt;Free curve trajectory number:VT_I2(=1 to 20)&gt; ,</p> <p>&lt;Viapoint : POSEDATA-C0(P,J) &gt;</p>                                                                                | None                                   | <p>SETSPLINEPOINT &lt;Free curve trajectory number&gt;</p> <p>&lt;Viapoint&gt;</p> <p>Registers viapoints in the free curve motion.</p>                                                                                          |
| GetSplinePoint | <p>&lt;Free curve trajectory number:VT_I2&gt; ,</p> <p>&lt;Viapoint number:VT_I4&gt;</p>                                                                                                 | <p>&lt;P type : VT_R4 VT_ARRAY&gt;</p> | <p>&lt;Approach (P) point&gt; = GETSPLINEPOINT (&lt;Free curve trajectory number&gt;, &lt;Viapoint number&gt;)</p> <p>Gets the viapoints for a registered free curve motion.</p>                                                 |

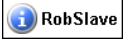
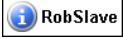
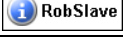
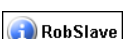
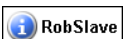
|                 |                                                                                                                             |                        |                                                                                                                                                                                                         |
|-----------------|-----------------------------------------------------------------------------------------------------------------------------|------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ClrSplinePoint  | <Free curve trajectory number:VT_I2 (=0 to 20)>                                                                             | None                   | CLRSPLINEPOINT <Free curve trajectory number><br>Clears all viapoints for free curvemotion.<br>                      |
| WaitSplinePoint | <Viapoint number:VT_I4>,<br><Waiting condition:VT_I2 (=0: command value, Not 0: encoder value)>                             | None                   | xdWAITSPLINE <Viapoint number>, <Waiting condition><br>Waits for the free curve to pass the designated viapoint.<br> |
| WaitMotionEnd   | None                                                                                                                        | None                   | Wait for robot motion end<br>                                                                                        |
| MotionSkip      | None                                                                                                                        | None                   | MotionSkip<br>Aborts running motion commands.<br>                                                                  |
| MotionComp      | None                                                                                                                        | VT_I2 0:running/1:done | MotionComp<br>Judges whether execution of running motion commands is complete.<br>                                 |
| Motor           | VT_I2 1:ON/0:OFF                                                                                                            | None                   | Motor ON/OFF<br>                                                                                                   |
| DefTool         | <no:VT_I2>,<P type: POSEDATA-C0>                                                                                            | None                   | For define tool in auto mode.<br>                                                                                  |
| DefWork         | <no:VT_I2>,<P type: POSEDATA-C0><br>[,<0:Normal/1:Fixed>]                                                                   | None                   | For define work in auto mode.<br>                                                                                  |
| DefArea         | <no:VT_I2>,<br>,<P type: POSEDATA-C0>,<br>,<V type: POSEDATA-C1>,<br><io:VT_I4>,<pos:VT_I4>,<err:VT_I4>,<enable:VT_I2(0,1)> | None                   | For define area in auto mode.<br>                                                                                  |

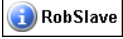
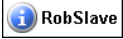
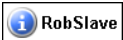
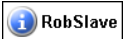
|          |                                                                                                                                                                                                                                                            |      |                                                                                                                                                                                                                                                                                                                                                                                  |
|----------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Draw     | <p>&lt; Interpolation method:VT_I2<br/>(=1:P, 2:L) &gt;<br/>&lt; [pass] vector : POSEDATA-C1&gt;<br/>[,option :VT_BSTR "NEXT"]</p>                                                                                                                         | None | <p>DRAW &lt;Interpolation<br/>method &gt;, &lt;pass&gt;<br/>(&lt;x&gt;,&lt;y&gt;,&lt;z&gt;)[, NEXT]<br/>Executes the relative<br/>movement designated in the<br/>work coordinate system.</p>                                                                                                  |
| DriveAEx | <p>&lt; [pass] (&lt;Axis1 number &gt;,<br/>&lt;Axis1<br/>coordinate&gt;):POSEDATA-C3&gt;,<br/>[(&lt;Axis2 number&gt;, &lt;Axis2<br/>coordinate&gt;),<br/>...<br/>[(&lt;Axis8 number&gt;, &lt;Axis8<br/>coordinate&gt;)]]<br/>[,option :VT_BSTR "NEXT"]</p> | None | <p>DRIVEA &lt;Pass start<br/>displacement&gt; (&lt;Axis1<br/>number&gt;, &lt;Axis1<br/>Coordinate&gt;), (&lt;Axis2<br/>number&gt;, &lt;Axis2<br/>Coordinate&gt;),...(&lt;Axis8<br/>number&gt;, &lt;Axis8<br/>Coordinate&gt;)[,NEXT]<br/>Executes the absolute<br/>motion of each axis.</p>  |
| DriveEx  | <p>&lt; [pass] (&lt;Axis1 number &gt;,<br/>&lt;Axis1<br/>coordinate&gt;):POSEDATA-C3&gt;,<br/>[(&lt;Axis2 number&gt;, &lt;Axis2<br/>coordinate&gt;),<br/>...<br/>[(&lt;Axis8 number&gt;, &lt;Axis8<br/>coordinate&gt;)]]<br/>[,option :VT_BSTR "NEXT"]</p> | None | <p>DRIVE &lt;Pass start<br/>displacement&gt; (&lt;Axis1<br/>number&gt;, &lt;Axis1<br/>Coordinate&gt;), (&lt;Axis2<br/>number&gt;, &lt;Axis2<br/>Coordinate&gt;),...(&lt;Axis8<br/>number&gt;, &lt;Axis8<br/>Coordinate&gt;)[,NEXT]<br/>Executes the relative motion<br/>of each axis.</p>   |

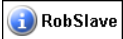
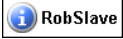
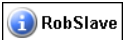
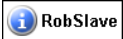
|            |                                                                                                                                                                                         |      |                                                                                                                                                                                                                                                                                                                                                             |
|------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| RotateH    | < [pass] <Relative rotation angle<br>around approach<br>vector>:POSEDATA-C2>,<br>[,option :VT_BSTR "NEXT"]                                                                              | None | ROTATEH <Pass start<br>displacement> <Relative<br>rotation angle around<br>approach vector> [,NEXT]<br>Executes rotary motion by<br>taking an approach vector as<br>an axis.<br>                                                                                         |
| Arrive     | <Motionratio:VT_R4>                                                                                                                                                                     | None | ARRIVE <Motionratio><br>Defines the motion ratio<br>relative to the programmed<br>full travel distance to the<br>target point in order to make<br>the current program stand by<br>to execute the next step until<br>the robot reaches the defined<br>motion ratio.<br> |
| PosClr     | <JntNumber:VT_I2>                                                                                                                                                                       | None | POSCLR <JntNumber><br>Forcibly restores the current<br>position of a joint to 0 mm<br>or 0 degree.<br>                                                                                                                                                                 |
| Interrupt  | <VT_I2:0:OFF 1:ON>                                                                                                                                                                      | None | INTERRUPT ON/OFF<br>Interrupts a robot motion.<br>                                                                                                                                                                                                                     |
| ST_aspACLD | <Mass of payload:VT_R4>,<br><Payload center of gravity<br>coordinate X :VT_R4>, <Payload<br>center of gravity coordinate<br>Y:VT_R4>, <Payload center of<br>gravity coordinate Z:VT_R4> | None | ST_aspACLD<br>Changes the internal load<br>condition values.<br>                                                                                                                                                                                                       |

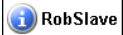
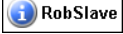
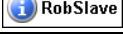
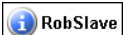
|                   |                                      |      |                                                                                                                                                                                                                                 |
|-------------------|--------------------------------------|------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_aspChange      | <Mode:VT_I2>                         | None | ST_aspChange<br>Selects the internal mode for proper control setting of motion optimization.<br>                                             |
| ST_SetGravity     | None                                 | None | ST_SetGravity<br>Compensates for the static load (gravity torque) applied to each joint and attains balance with gravity torque.<br>         |
| ST_ResetGravity   | None                                 | None | ST_ResetGravity<br>Disables the balance setting between the limited motor torque and gravity torque, which is made with ST_SetGravity.<br> |
| ST_SetGrvOffset   | None                                 | None | ST_SetGrvOffset<br>Compensates the torque of each joint programmed with ST_SetGravity for gravity torque.<br>                              |
| ST_ResetGrvOffset | None                                 | None | ST_ResetGrvOffset<br>Disables the gravity offset function.<br>                                                                             |
| ST_SetCurLmt      | <AxisNumber:VT_I2>,<br><Value:VT_R4> | None | ST_SetCurLmt<br>Sets the limit of motor current to be applied to the specified axis.<br>                                                   |

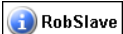
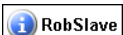
|                    |                                      |      |                                                                                                                                                                                                   |
|--------------------|--------------------------------------|------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_ResetCurLmt     | <AxisNumber:VT_I2>                   | None | ST_ResetCurLmt<br>Resets the motor current limit of the specified axis.<br>                                    |
| ST_SetEralw        | <AxisNumber:VT_I2>,<br><Value:VT_R4> | None | ST_SetEralw<br>Modifies the allowable deviation of the specified axis.<br>                                     |
| ST_ResetEralw      | <AxisNumber:VT_I2>                   | None | ST_ResetEralw<br>Resets the allowable deviation value of the specified axis to the initial value.<br>          |
| ST_OnSrvLock       | <specified axis:VT_I2>               | None | ST_OnSrvLock<br>Servo-locks a specified axis (exclusively designed for four-axis robots).<br>                |
| ST_OffSrvLock      | <specified axis:VT_I2>               | None | ST_OffSrvLock<br>Releases servo lock for the specified axis (exclusively designed for four-axis robots).<br> |
| ST_SetCompControl  | None                                 | None | ST_SetCompControl<br>Enables the compliance function (exclusively designed for 6-axis robots).<br>           |
| ST_SetCompFControl | None                                 | None | ST_SetCompFControl<br>Enables the compliance control function (exclusively designed for 6-axis robots).<br>  |

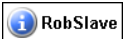
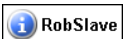
|                     |                                                                                                                                                                                                         |      |                                                                                                                                                                                                             |
|---------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_ResetCompControl | None                                                                                                                                                                                                    | None | ST_ResetCompControl<br>Disables the compliance control function (exclusively designed for 6-axis robots).<br>            |
| ST_SetFrcCoord      | <Set value:VT_R4>                                                                                                                                                                                       | None | ST_SetFrcCoord<br>Selects a force limiting coordinate system (exclusively designed for 6-axis robots).<br>               |
| ST_SetFrcLimit      | <Limiting rate along X:VT_R4>,<br><Limiting rate along Y:VT_R4>,<br><Limiting rate along Z:VT_R4>,<br><Limiting rate about X:VT_R4>,<br><Limiting rate about Y:VT_R4>,<br><Limiting rate about Z:VT_R4> | None | ST_SetFrcLimit<br>Sets the force limiting rates (exclusively designed for 6-axis robots).<br>                          |
| ST_ResetFrcLimit    | None                                                                                                                                                                                                    | None | ST_ResetFrcLimit<br>Initializes the force limiting rates (exclusively designed for 6-axis robots).<br>                 |
| ST_SetCompRate      | <Compliance along X:VT_R4>,<br><Compliance along Y:VT_R4>,<br><Compliance along Z:VT_R4>,<br><Compliance about X:VT_R4>,<br><Compliance about Y:VT_R4>,<br><Compliance about Z:VT_R4>                   | None | ST_SetCompRate<br>Sets the compliance rates under the compliance control (exclusively designed for 6-axis robots).<br> |
| ST_ResetCompRate    | None                                                                                                                                                                                                    | None | ST_ResetCompRate<br>Initializes the compliance rates (exclusively designed for 6-axis robots).<br>                     |

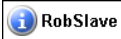
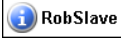
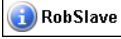
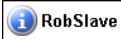
|                    |                                                                                                                                                                                                               |      |                                                                                                                                                                                                                                                                      |
|--------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_SetFrcAssist    | <Force assistance along X:VT_R4>, <Force assistance along Y:VT_R4>, <Force assistance along Z:VT_R4>, <Moment assistance about X:VT_R4>, <Moment assistance about Y:VT_R4>, <Moment assistance about Z:VT_R4> | None | ST_SetFrcAssist<br>Sets the force assistance under the compliance control (special compliance control function statement) (exclusively designed for 6-axis robots).<br>           |
| ST_ResetFrcAssist  | None                                                                                                                                                                                                          | None | ST_ResetFrcAssist<br>Initializes the force assistance (special compliance control function statement) (exclusively designed for 6-axis robots).<br>                              |
| ST_SetCompJLimit   | <J1 current limit :VT_R4>, <J2 current limit :VT_R4>, <J3 current limit :VT_R4>, <J4 current limit :VT_R4>, <J5 current limit :VT_R4>, <J6 current limit :VT_R4>                                              | None | ST_SetCompJLimit<br>Sets the current limit under the compliance control (special compliance control function statement) (exclusively designed for 6-axis robots).<br>           |
| ST_ResetCompJLimit | None                                                                                                                                                                                                          | None | ST_ResetCompJLimit<br>aInitializes the current limit under the compliance control (special compliance control function statement) (exclusively designed for 6-axis robots).<br> |

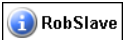
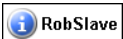
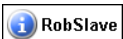
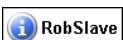
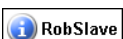
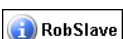
|                   |                                                                                                                                                                                                                                                                                                            |      |                                                                                                                                                                                                                                                                                         |
|-------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_SetCompVMode   | None                                                                                                                                                                                                                                                                                                       | None | <p>ST_SetCompVMode</p> <p>Sets the velocity control mode under the compliance control (special compliance control function statement) (exclusively designed for 6-axis robots).</p>                  |
| ST_ResetCompVMode | None                                                                                                                                                                                                                                                                                                       | None | <p>ST_ResetCompVMode</p> <p>Disables the velocity control mode under the compliance control (special compliance control function statement) (exclusively designed for 6-axis robots).</p>           |
| ST_SetCompEralw   | <p>&lt;Allowable deviation X :VT_R4&gt;,<br/>         &lt;Allowable deviation Y :VT_R4&gt;,<br/>         &lt;Allowable deviation Z :VT_R4&gt;,<br/>         &lt;Allowable deviation X :VT_R4&gt;,<br/>         &lt;Allowable deviation Y :VT_R4&gt;,<br/>         &lt;Allowable deviation Z :VT_R4&gt;</p> | None | <p>ST_SetCompEralw</p> <p>Sets the allowable deviation values of the position and the posture of the tool tip under the compliance control (exclusively designed for 6-axis robots).</p>           |
| ST_ResetCompEralw | None                                                                                                                                                                                                                                                                                                       | None | <p>ST_ResetCompEralw</p> <p>Initializes the allowable deviation values of the position and the posture of the tool end under the compliance control (exclusively designed for 6-axis robots).</p>  |

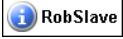
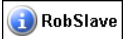
|                  |                                                                                                                                                                           |      |                                                                                                                                                                                                                 |
|------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| ST_SetDampRate   | <DampRate along X:VT_R4>,<br><DampRate along Y:VT_R4>,<br><DampRate along Z:VT_R4>,<br><DampRate about X:VT_R4>,<br><DampRate about Y:VT_R4>,<br><DampRate about Z:VT_R4> | None | ST_SetDampRate<br>Sets the damping rates under the compliance control (exclusively designed for 6-axis robots).<br>          |
| ST_ResetDampRate | None                                                                                                                                                                      | None | ST_ResetDampRate<br>Initializes the damping rates under the compliance control (exclusively designed for 6-axis robots).<br> |
| ST_SetZBalance   | None                                                                                                                                                                      | None | ST_SetZBalance<br>Sets the gravity compensation value of the Z and T axes (exclusively designed for 4-axis robots).<br>    |
| ST_ResetZBalance | None                                                                                                                                                                      | None | ST_ResetZBalance<br>Disables the gravity compensation function (exclusively designed for 4-axis robots).<br>               |
| DELAY            | <value:VT_I2>                                                                                                                                                             | None | Msec<br>Suspends program processing for a designated period time.<br>                                                      |
| SYSSTATE         | None                                                                                                                                                                      | None | SYSSTATE<br>Gets the system status of the robot controller.<br>                                                            |

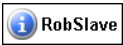
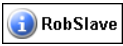
|      |                      |                              |                                                                                                                                                                        |
|------|----------------------|------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| J2P  | <J type:POSEDATA-C0> | <P type:<br>VT_R4 VT_ARRAY>  | J2P<br>Transforms joint type data to position type data.<br>                        |
| J2T  | <J type:POSEDATA-C0> | <T type :<br>VT_R4 VT_ARRAY> | J2T<br>Transforms joint type data to homogeneous transformation type data.<br>      |
| P2J  | <P type:POSEDATA-C0> | <J type:<br>VT_R4 VT_ARRAY>  | P2J<br>Transforms position type data to joint type data.<br>                        |
| P2T  | <P type:POSEDATA-C0> | <T type :<br>VT_R4 VT_ARRAY> | P2T<br>Transforms position type data to homogeneous transformation type data.<br> |
| T2J  | <T type:POSEDATA-C0> | <J type:<br>VT_R4 VT_ARRAY>  | T2J<br>Transforms homogeneous transformation type data to joint type data.<br>    |
| T2P  | <T type:POSEDATA-C0> | <P type:<br>VT_R4 VT_ARRAY>  | T2P<br>Transforms homogeneous transformation type data to position type data.<br> |
| TINV | <T type:POSEDATA-C0> | <T type :<br>VT_R4 VT_ARRAY> | TINV<br>Calculates an inverse matrix of homogeneous transformation type data.<br> |

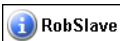
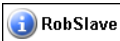
|         |                                                       |                                 |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |
|---------|-------------------------------------------------------|---------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| NORMTRN | <T type:POSEDATA-C0>                                  | <T<br>type :VT_R4 VT_ARRA<br>Y> | NORMTRN<br>Normalizes<br>homogeneous-transformatio<br>n data.                                                                                                                                                                                                                                                                                                                                                                                                                   |
| TMUL    | <T type n1 :POSEDATA-C0>,<br><T type n2 :POSEDATA-C0> | <T type :<br>VT_R4 VT_ARRAY>    | =T<n1> * T<n2><br>Matrix operation for<br>transformation type data.<br>                                                                                                                                                                                                                                                                                                                      |
| DEVH    | <P type n1:POSEDATA-C0>,<br><P type n2:POSEDATA-C0>   | <P type:<br>VT_R4 VT_ARRAY>     | Calculates destination<br>coordinates based on tool<br>coordinates.<br><br>If n1>1 then<br>=P<n1> + (P<n2>.x,<br>P<n2>.y, P<n2>.z,<br>P<n2>.rx, P<n2>.ry,<br>P<n2>.rz )H<br><br>If n1=0 then<br>=DESTPOS + (P<n2>.x,<br>P<n2>.y, P<n2>.z,<br>P<n2>.rx, P<n2>.ry,<br>P<n2>.rz )H<br><br>If n1=-1 then<br>=CURPOS + (P<n2>.x,<br>P<n2>.y, P<n2>.z,<br>P<n2>.rx, P<n2>.ry,<br>P<n2>.rz )H<br> |

|                     |                                                                                                                                                     |                                                                                                                              |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                        |
|---------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------------------------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| DEV                 | <p>&lt;P type n1:POSEDATA-C0&gt;,<br/>&lt;P type n2:POSEDATA-C0&gt;</p>                                                                             | <p>&lt;P type:<br/>VT_R4 VT_ARRAY&gt;</p>                                                                                    | <p>Calculates destination coordinates based on base coordinates.</p> <p>If <math>n1 &gt; 1</math> then<br/> <math>=P_{&lt;n1&gt;} + (P_{&lt;n2&gt;}.x,</math><br/> <math>P_{&lt;n2&gt;}.y, P_{&lt;n2&gt;}.z,</math><br/> <math>P_{&lt;n2&gt;}.rx, P_{&lt;n2&gt;}.ry,</math><br/> <math>P_{&lt;n2&gt;}.rz)</math></p> <p>If <math>n1 = 0</math> then<br/> <math>=DESTPOS + (P_{&lt;n2&gt;}.x,</math><br/> <math>P_{&lt;n2&gt;}.y, P_{&lt;n2&gt;}.z,</math><br/> <math>P_{&lt;n2&gt;}.rx, P_{&lt;n2&gt;}.ry,</math><br/> <math>P_{&lt;n2&gt;}.rz)</math></p> <p>If <math>n1 = -1</math> then<br/> <math>=CURPOS + (P_{&lt;n2&gt;}.x,</math><br/> <math>P_{&lt;n2&gt;}.y, P_{&lt;n2&gt;}.z,</math><br/> <math>P_{&lt;n2&gt;}.rx, P_{&lt;n2&gt;}.ry,</math><br/> <math>P_{&lt;n2&gt;}.rz)</math></p>  |
| TrackDataInitialize | <Initialization mode:VT_I2>                                                                                                                         | None                                                                                                                         | <p>TRACKDATAINITIALIZE</p> <p>Initializes data within the conveyer tracking data buffer.</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                      |
| TrackDataSet        | <p>&lt;conveyer_number:VT_I2&gt;,&lt;num<br/>ber_of_recognized_workpieces:VT<br/>_I2&gt;,&lt;recognized_workpiece_posit<br/>ion:POSEDATA-C0&gt;</p> | None                                                                                                                         | <p>TRACKDATASET</p> <p>Saves data in the conveyer tracking buffer.</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                            |
| TrackDataGet        | <conveyer_number:VT_I2>,<data_<br>number:VT_I2>                                                                                                     | <p>&lt;number_of_remaining<br/>data_items:VT_I2&gt;,<br/>&lt;recognized_workpiece_<br/>position:<br/>VT_R4 VT_ARRAY &gt;</p> | <p>TRACKDATAGET</p> <p>Obtains data from the conveyer tracking buffer.</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                        |

|                 |                                                                                            |                                                                                                           |                                                                                                                                                                                      |
|-----------------|--------------------------------------------------------------------------------------------|-----------------------------------------------------------------------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| TrackDataInfo   | <conveyer_number:VT_I2>,<data_number:VT_I2>                                                | <encoder_value_at_recognition:VT_I4>,<availability:VT_I2>,<recognized_workpiece_position:VT_R4 VT_ARRAY > | TRACKDATAINFO<br>Obtains information within the conveyer tracking buffer.<br>                     |
| TrackDataNum    | <conveyer_number:VT_I2>                                                                    | <number_of_saved_data_items:VT_I2>                                                                        | TRACKDATANUM<br>Obtains the number of data items retained with TRACKDATASET.<br>                  |
| CurTrackPos     | <conveyer_number:VT_I2>,<recognized_workpiece_position P type:POSEDATA-C0>,<mode:VT_I2>    | <position:VT_R4 VT_ARRAY >                                                                                | CURTRACKPOS<br>Obtains the position of the workpiece subject to tracking as a P type.<br>         |
| CurTrackPosEx   | <conveyer_number:VT_I2>,<recognized_workpiece_position P type:POSEDATA-C0>,<mode:VT_I2>    | <position:VT_R4 VT_ARRAY >                                                                                | CURTRACKPOSEX<br>Obtains a tracking-target workpiece position in the P-type form.<br>           |
| WaitTrackMove   | <conveyer_number:VT_I2>,<recognized_workpiece_position P type:POSEDATA-C0>,<timeout:VT_I2> | None                                                                                                      | WAITTRACKMOVE<br>Waits for tracking-target workpiece to enter into a tracking start area.<br>   |
| WaitTrackMoveEx | <conveyer_number:VT_I2>,<recognized_workpiece_position P type:POSEDATA-C0>,<timeout:VT_I2> | <error_information:VT_I2>                                                                                 | WAITTRACKMOVEEX<br>Waits for tracking-target workpiece to enter into a tracking start area.<br> |
| CurTrackSpd     | <conveyer_number:VT_I2>                                                                    | <conveyer_speed:VT_R4 >                                                                                   | CURTRACKSPD<br>Obtains the speed of the conveyer specified in <conveyer_number>.<br>            |

|                   |                                                                                                                                             |                             |                                                                                                                                                                                  |
|-------------------|---------------------------------------------------------------------------------------------------------------------------------------------|-----------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| CalcWorkPos       | <conveyer_number:VT_I2>,<work piece_position_at_recognition: P type:POSEDATA-C0>,<encode_value_at_recognition:VT_I4>                        | <position: VT_R4 VT_ARRAY > | CALCWORKPOS<br>Obtains the current position of the specified workpiece.<br>                   |
| SetTrackMove      | <conveyer_number:VT_I2>                                                                                                                     | None                        | SETTRACKMOVE<br>Starts the tracking operation for the specified conveyer.<br>                 |
| ResetTrackMove    | None                                                                                                                                        | None                        | RESETTRACKMOVE<br>Switches from the tracking operation mode to the normal operation mode.<br> |
| SetTrackStartArea | <conveyer_number:VT_I2>,<conveyer_upstream(-)side_tracking_start_position:VT_I2>,<conveyer_downstream(+)side_tracking_start_position:VT_I2> | None                        | SETTRACKSTARTAREA<br>Sets the tracking start range at the time of WAITTRACKMOVE.<br>        |
| ClearSrvLog       | None                                                                                                                                        | None                        | Clearness of single axis control log<br>=PAC:ClearSrvMonitor                                                                                                                     |
| StartSrvLog       | None                                                                                                                                        | None                        | Beginning of single axis control log<br>=PAC:StartSrvMonitor                                                                                                                     |
| StopSrvLog        | None                                                                                                                                        | None                        | End of single axis control log<br>=PAC:StopSrvMonitor                                                                                                                            |
| SetSrvLogCond     | <Axis number : VT_I2>,<Data number 1:VT_I2>,<Data number 2 : VT_I2>,<Sampling rate : VT_I2>                                                 | None                        | Condition setting of single axis control log<br>=PAC:SetMonitorCond                                                                                                              |

|                       |                                             |                                                                                                                       |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                           |
|-----------------------|---------------------------------------------|-----------------------------------------------------------------------------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| GetSrvLogCond         | None                                        | <Axis number : VT_I2>,<Data number 1 : VT_I2>,<Data number 2 : VT_I2>,<Sampling rate : VT_I2>,<Sampling counts:VT_I2> | Condition acquisition of single axis control log                                                                                                                                                                                                                                                                                                                                                                                                                                                                          |
| GetSrvLog             | None                                        | <Servo data (Two dimension array): VT_R4   VT_ARRAY>                                                                  | Acquisition of single axis control log                                                                                                                                                                                                                                                                                                                                                                                                                                                                                    |
| TakeArm               | <Arm group : VT_I4> [, <Keep option:VT_I4>] | None                                                                                                                  | TakeArm<br><Keep option>:= 0 (default):<br>0: The tool coordinate and the work coordinate are returned to the origin, and the internal speed, the internal acceleration, and the internal deceleration are set to 100.<br>1: The tool coordinate, the work coordinate, the internal speed, the internal acceleration, and the internal deceleration are maintained to their current setting.<br>Obtains visual process priority.<br> |
| GiveArm               | None                                        | None                                                                                                                  | GiveArm<br>Releases robot control priority.<br>                                                                                                                                                                                                                                                                                                                                                                                      |
| SetHighPathAccuracy   | None                                        | None                                                                                                                  | High path accuracy mode ON                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                |
| ResetHighPathAccuracy | None                                        | None                                                                                                                  | High path accuracy mode OFF                                                                                                                                                                                                                                                                                                                                                                                                                                                                                               |

|                     |                                                                                 |                             |                                                                                                                                                                                                       |
|---------------------|---------------------------------------------------------------------------------|-----------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| SetSingularAvoid    | <Mode: VT_I2 = 0:OFF, 1:ON>                                                     | None                        | Singular-point avoidance mode ON/OFF<br><Mode> = 0:OFF, 1:ON                                                                                                                                          |
| FigAprp             | <Reference position : POSEDATA-C0 (P type only)> ,<br><Approach length : VT_R4> | <Fig:VT_I2>                 | FIGAPRP<br>Calculates figures at an approach position and a standard position available to move in PTP motion.<br> |
| FigAprl             | <Reference position : POSEDATA-C0 (P type only)> ,<br><Approach length : VT_R4> | <Fig:VT_I2>                 | FIGAPRL<br>Calculates figures at an approach position and a standard position available to move in CP motion.<br>  |
| GetCollisionForce   | None                                                                            | <Max value: VT_R4 VT_ARRAY> | Get a maximum external force value.                                                                                                                                                                   |
| ClearCollisionForce | None                                                                            | None                        | Clear a maximum external force value.                                                                                                                                                                 |
| ResetCollisionJnt   | <Axis No: VT_I2>                                                                | None                        | Disable collision detection for the specified axis                                                                                                                                                    |
| SetCollisionJnt     | <Axis No: VT_I2>                                                                | None                        | Enable collision detection for the specified axis.                                                                                                                                                    |
| SetCollisionLevel   | <Axis No: VT_I2>,<br><Detection Level: VT_I4(1 ~ 500)>                          | None                        | Set collision detection level.                                                                                                                                                                        |
| SetExtForceDetect   | <Enable: VT_I2(0/1)>                                                            | None                        | Enable/Disable collision detection.                                                                                                                                                                   |
| RPM                 | <Axis No: VT_I2>,<br><RPM value: VT_R4>                                         | <SPEED value (%): VT_R4>    | Convert the rotation speed of the specified joint, which is specified in rpm, to the percentage (%) of the maximum internal speed in PTP motion.                                                      |

|     |                    |                             |                                                                                                               |
|-----|--------------------|-----------------------------|---------------------------------------------------------------------------------------------------------------|
| MPS | <MPS value: VT_R4> | <SPEED value (%):<br>VT_R4> | Convert the speed value specified in mm/sec to the percentage (%) of the maximum internal speed in CP motion. |
|-----|--------------------|-----------------------------|---------------------------------------------------------------------------------------------------------------|

The argument of the Execute method of the CaoRobot class specifies command number + parameter by the VARIANT array.

Example:

```
Dim vRes as Variant
vRes=caoRobot.Execute("GetJntData",Array(1,6)) ' 6th joint motor current speed[rpm]
caoRobot.Execute("ExtSpeed",Array(50.0, 25.0, 25.0) )
'external speed =50%, acceleration =25%, deceleration =25%
caoRobot.Execute "APPROACH", Array(1, "P11", "@P 100", "NEXT")
'APPROACH P, P11, @P 100, NEXT
```

The user can enhance an original command by defining an additional command in the UserExtention program of the UserExtention.pac file, and describing the execution code corresponding to it. Following is an concrete code example when GETSRVDATA and the GETJNTDATA command are added

### 1. UserExtention.pac and RobSlave.h are acquired.

Refer to ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Bin¥ folder.

### 2. Define the corresponding command number into RobSlave.h.

Define the corresponding command number and add it into RobSlave.h.

The value of RBS\_CMD\_EXTENTION is 10000. It is defined by RobSlave.h.

```
'User Extention Commands Def.
'-----
#define RBS_CMDEX_APPROACH_L (RBS_CMD_EXTENTION +1)
#define RBS_CMDEX_APPROACH_P (RBS_CMD_EXTENTION +2)
#define RBS_CMDEX_GETSRVDATA (RBS_CMD_EXTENTION +3)
#define RBS_CMDEX_GETJNTDATA (RBS_CMD_EXTENTION +4)
```

### 3. Describe the execution code to an additional command.

Pv.x (=T[RBS\_IDX\_COMMAND].X) stores execution command ID. Refer this value and branch to the actual execution code using SELECT-CASE statement. Command arguments are stored in pv.Y, pv.Z, ov.X, ov.Y, ov.Z, av.X, av.Y, and av.Z (= T[RBS\_IDX\_COMMAND]. Y and Z etc.).

```
' User Extention Commands Impl.
'-----
PROGRAM UserExtention(pv as VECTOR, ov as VECTOR, av as VECTOR)
  DEFSNG ret
  DEFINIT index, path
  DEFINIT vartype, varindex
  DEFSNG length
  DEFJNT jv

  select case POSX(pv)
```

```

        case RBS_CMDEX_GETJNTDATA          'GetJntData(<Index>, <JontNo>)
            LETX T[RBS_IDX_RESULT] = GetJntData ( POSY(pv), POSZ(pv) )
            I[RBS_IDX_STATE] = RBS_STA_RETVAL ' Return value
        case RBS_CMDEX_GETSRVDATA          'GetSrvData(<Index>)
            jv = GetSrvData ( POSY(pv) )
#ifdef __VERTICAL_ROBOT__
            T[RBS_IDX_RESULT] = ( JOINT(1, jv), JOINT(2, jv), JOINT(3, jv), JOINT(4, jv), JOINT(5, jv),
JOINT(6, jv), 0, 0, 0, -1 )
#else
            T[RBS_IDX_RESULT] = ( JOINT(1, jv), JOINT(2, jv), JOINT(3, jv), JOINT(4, jv), 0, 0, 0, 0, 0, -1 )
#endif
            I[RBS_IDX_STATE] = RBS_STA_RETVAL ' Return value
        case else
            I[RBS_IDX_STATE] = RBS_STA_ERR
        end select

```

If the call does not return value, set I[RBS\_IDX\_STATE] = RBS\_STA\_DONE.

When a value is returned, substitute the value in T[RBS\_IDX\_RESULT] and set I[RBS\_IDX\_STATE] = RBS\_STA\_RETVAL. In this case, Execute method of CaoRobot class will have return value of VARIANT array, and each elements of T[RBS\_IDX\_RESULT] is stored in the array.

#### 4. Update CRC32 information of the UserExtention.pac file.

CRC32 information of UserExtension.pac is recorded in RobSlave.h.

```

.CRC code
#define RBS_SLVCRC_CODE11          &H62cb2dc4
#define RBS_EXTCRC_CODE          &H1e5d8368

```

Calculate CRC32 of UserExtension.pac and update the value of RBS\_EXTCRC\_CODE.

Otherwise, the error occurs when the operation command is executed.

The value of CRC32 can be acquired in the @CRC system variable of the CaoFile class.

#### 5. Execute CaoRobot::Execute method with “UserExt” command.

Command=“UserExt”

Parameter=<additional command >,<arg1>,<arg2>,... (array of VARIANT)

Example: vRes = CaoRobot.Execute( “UserExt”, Array(10004, 1, 6 ) ) ‘= GetJntData(1,6)

### 【 essential requisites 】

At the current implementation, “RobSlave.pac” and “UserExtention.pac” programs need to be executed beforehand on the robot controller to execute Execute method of CaoRobot class. RobSlave.pac and UserExtention.pac are in ORiN2¥CAO¥ProviderLib¥DENSO¥NetwoRC¥Bin.

#### 4.2.40. CaoTask::AddVariable method

The argument of the AddVariable method of the CaoTask class specifies the system variable name.

Please refer Table 4-13 for the list of implemented system variables.

<sup>11</sup> CRC32 of RobSlave.pac

**4.2.41. CaoTask::get\_VariableNames property**

A list of the variable identifier and the system variable identifier that can be specified by the AddVariable method is acquired.

**4.2.42. CaoTask::Start method**

Start PAC program corresponding to the object.

This method has the following two arguments.

**Syntax** Start <lMode:LONG>, <bstrOpt:BSTR>

|         |   |      |                                                                                                                    |
|---------|---|------|--------------------------------------------------------------------------------------------------------------------|
| lMode   | : | [in] | Start mode                                                                                                         |
|         |   |      | 1: One cycle execution, 2: Cyclic execution, 3: One step forward,<br><del>4: 1 Step backward</del> , 5: Resume all |
| bstrOpt | : | [in] | Option character string (unused)                                                                                   |

If this method is called with mode 5 (Resume), then all suspended programs in the robot controller are resumed.

**4.2.43. CaoTask::Stop method**

Stop PAC program corresponding to the object. This method has the following two arguments.

**Syntax** Stop <lMode:LONG>, <bstrOpt:BSTR>

|         |   |      |                                                                                                       |
|---------|---|------|-------------------------------------------------------------------------------------------------------|
| lMode   | : | [in] | Stop mode                                                                                             |
|         |   |      | 0: Default stop, 1: Instant stop, 2: Step stop, 3: Cycle stop, 4:<br>Initialized stop, 5: Suspend all |
| bstrOpt | : | [in] | Option character string (unused)                                                                      |

“0: Default stop” is the same as “1: Instant stop”.

If this method is called with mode 5 (Suspend), then all programs in the robot controller are suspended.

**4.2.44. CaoVariable::get\_Value property**

Get the value of the variable that corresponds to the object.

Please refer 2.3 for implementation situation and supported data type.

**4.2.45. CaoVariable::put\_Value property**

Set the value of the variable that corresponds to the object.

Please refer 2.3 for implementation situation and supported data type.

**4.2.46. CaoVariable::put\_ID property**

Set the index of the variable that corresponds to the object.

This property can be used for the object created with '\*'.

Example (VB):

|                                            |                                    |
|--------------------------------------------|------------------------------------|
| Set objIO = caoCtrl.AddVariable( "IO[*]" ) | ' Specify a wild card (*) for I/O. |
| objIO.ID = 128                             | ' Specify the index by ID property |
| boolValue = objIO.Value                    | ' get IO[128] value                |

#### 4.2.47. CaoVariable::get\_ID property

Get the index of the variable that corresponds to the object.

#### 4.2.48. CaoVariable::get\_Microsecond property

Get time stamp of the variable corresponding to the object.

Time stamp counter is incremented by one on every 500 microsecond after controller boot, with counter value 0 at the controller startup.

As the counter value increases, the value goes around as following.

0,1,2→2147483647(0x7fffffff) ,-2147483648(0x80000000) ,-2147483647(0x80000001) →-2,-1,0

[Note] If the object does not support time stamp, the property returns 0.

#### 4.2.49. CaoMessage::Clear method

Clear the occurring error status by using the Clear method of the CaoController class.

### 4.3. Variable list

#### 4.3.1. Controller class

**Table 4-10 Controller class user variable list**

| Variable identifier | Data type           | Explanation                                                                                                      | Attribute |     |
|---------------------|---------------------|------------------------------------------------------------------------------------------------------------------|-----------|-----|
|                     |                     |                                                                                                                  | get       | put |
| I                   | VT_I4               | I type variable. The variable number is specified behind the variable name.                                      | √         | √   |
| F                   | VT_R4               | F type variable. The variable number is specified behind the variable name.                                      | √         | √   |
| D                   | VT_R8               | D type variable. The variable number is specified behind the variable name.                                      | √         | √   |
| V                   | VT_ARRAY<br>  VT_R4 | V type variable. The variable number is specified behind the variable name.<br>The data type has three elements. | √         | √   |
| P                   | VT_ARRAY<br>  VT_R4 | P type variable. The variable number is specified behind the variable name.<br>The data type has seven elements. | √         | √   |
| J                   | VT_ARRAY<br>  VT_R4 | J type variable. The variable number is specified behind the variable name.<br>The data type has six elements.   | √         | √   |
| T                   | VT_ARRAY<br>  VT_R4 | T type variable. The variable number is specified behind the variable name.<br>The data type has ten elements.   | √         | √   |
| S                   | VT_BSTR             | S type variable. The variable number is specified behind the variable name.                                      | √         | √   |
| IO                  | VT_BOOL             | IO type variable. The variable number is specified behind the variable name.                                     | √         | √   |
| TOOL                | VT_ARRAY<br>  VT_R4 | TOOL. The variable number (0 or greater) is specified behind the variable name.                                  | √         | √   |
| WORK                | VT_ARRAY<br>  VT_R4 | WORK. The variable number (0 or greater) is specified behind the variable name.                                  | √         | √   |

|      |                     |                                                                                                                                                                                                                                                                                                           |   |   |
|------|---------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|---|---|
| AREA | VT_ARRAY<br>  VT_R4 | AREA. The variable number (0 or greater) is specified behind the variable name.<br>(V[0],...,V[8],IO,Pos,Err,Enable)<br>V[0]~V[8]:        area<br>IO        :        I/O port number<br>Pos       :        position number<br>Err       :        error flag<br>Enable    :        function enable/disable | √ | √ |
| _ITP | VT_I4               | ITPCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _PAC | VT_I4               | PACCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _DIO | VT_I4               | DIOCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _ARM | VT_I4               | ARMCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _SRV | VT_I4               | SRVCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _SPD | VT_I4               | SPDCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _VIS | VT_I4               | VISCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |
| _COM | VT_I4               | COMCNF . The variable number is specified behind the variable name.                                                                                                                                                                                                                                       | √ | √ |

Table 4-11 Controller class system variable list

| Variable identifier | Data type | Explanation                                              | Attribute |     |
|---------------------|-----------|----------------------------------------------------------|-----------|-----|
|                     |           |                                                          | get       | put |
| @CURRENT_TIME       | VT_DATE   | Current time held in the controller                      | √         | √   |
| @FREE_USER_MEM      | VT_I4     | Free user memory size (byte)                             | √         | ×   |
| @NORMAL_STATUS      | VT_BOOL   | true = normal, false = abnormal (an error is occurring.) | √         | ×   |
| @AUTO_MODE          | VT_BOOL   | true = automatic mode, false = not in automatic mode     | √         | ×   |

|                    |         |                                                                           |   |   |
|--------------------|---------|---------------------------------------------------------------------------|---|---|
| @MODE              | VT_I2   | 1: manual, 2: teach check, 3: auto, 4: external auto                      | √ | × |
| @BUSY_STATUS       | VT_BOOL | true = program is executed.<br>False = program is not executed.           | √ | × |
| @EMERGENCY_STOP    | VT_BOOL | true = emergency stop is active.<br>False = emergency stop is not active. | √ | × |
| @ERROR_CODE        | VT_I4   | Currently occurring error code.<br>Returns 0 if no error is occurring     | √ | × |
| @ERROR_CODE_HEX    | VT_BSTR | Currently occurring error code by hexadecimal character string.           | √ | × |
| @ERROR_LEVEL       | VT_I4   | Currently occurring error level.                                          | √ | × |
| @ERROR_DESCRIPTION | VT_BSTR | Currently occurring error description.                                    | √ | × |
| @MAKER_NAME        | VT_BSTR | “DENSO CORPORATION”                                                       | √ | × |
| @TYPE              | VT_BSTR | “NetwoRC Controller”                                                      | √ | × |
| @VERSION           | VT_BSTR | Controller’s version                                                      | √ | × |
| @SERIAL_NO         | VT_BSTR | Controller’s serial number                                                | √ | × |

## 4.3.2. Robot class

Table 4-12 Robot class system variable list

| Variable identifier   | Data type           | Explanation                                                                                                             | Attribute |     |
|-----------------------|---------------------|-------------------------------------------------------------------------------------------------------------------------|-----------|-----|
|                       |                     |                                                                                                                         | get       | put |
| @CURRENT_POSITION     | VT_ARRAY<br>  VT_R4 | Current robot position. The unit is arbitrary.<br>P type variable.                                                      | √         | ×   |
| @CURRENT_ANGLE        | VT_ARRAY<br>  VT_R4 | Current robot position (each axis value). The unit is arbitrary. J type variable                                        | √         | ×   |
| @SERVO_ON             | VT_BOOL             | True = servo ON, false = servo OFF                                                                                      | √         | ×   |
| @ZERO_RETURN_REQUIRED | VT_BOOL             | True = zero return is necessary, false = zero return is not necessary.                                                  | √         | ×   |
| @BUSY_STATUS          | VT_BOOL             | true=arm moving, false=arm stopping                                                                                     | √         | ×   |
| @TYPE_NAME            | VT_BSTR             | Robot type name<br>“VM-D”, “VS-D”, “VSS-D”, “DM-D”, “Unknown”                                                           | √         | ×   |
| @TYPE                 | VT_I4               | Robot type data                                                                                                         | √         | ×   |
| @CURRENT_TRANS        | VT_ARRAY<br>  VT_R4 | Current robot position expressed in T type                                                                              | √         | ×   |
| @CURRENT_TOOL         | VT_I2               | Currently used tool number                                                                                              | √         | ×   |
| @CURRENT_WORK         | VT_I2               | Currently used work number                                                                                              | √         | ×   |
| @SPEED                | VT_R4               | Internal speed  2.330              | √         | ×   |
| @ACCEL                | VT_R4               | Internal acceleration  2.330       | √         | ×   |
| @DECEL                | VT_R4               | Internal deceleration  2.330       | √         | ×   |
| @JSPEED               | VT_R4               | Internal joint speed  2.330        | √         | ×   |
| @JACCEL               | VT_R4               | Internal joint acceleration  2.330 | √         | ×   |
| @JDECEL               | VT_R4               | Internal joint deceleration  2.330 | √         | ×   |
| @EXTSPEED             | VT_R4               | External speed                                                                                                          | √         | ×   |
| @EXTACCEL             | VT_R4               | External acceleration                                                                                                   | √         | ×   |

|                        |                     |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                              |   |   |
|------------------------|---------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|---|---|
| @EXTDECEL              | VT_R4               | External deceleration                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                        | √ | × |
| @HIGH_CURRENT_POSITION | VT_ARRAY<br>  VT_R4 | <p>Current robot position. The unit is arbitrary.<br/>P type variable.</p> <p>The value is indefinite under machine-locked because it is retrieved from an encoder directly.</p> <p> <b>2.330</b></p> <p>When the controller is not in machine-lock mode, the current encoder value is returned. (update resolution: 500 microsecond)</p> <p>When the controller is in machine-lock mode, the internal position target value is returned. (update resolution: 8 msec)</p> <p>The time stamp of data acquisition can be referred by Microsecond property of CaoVariable class.</p> <p>[Note]</p> <p>Controllers prior to Version 2.90 do not support time stamp. On machine-lock mode, current position is indefinite.</p> | √ | × |
| @HIGH_CURRENT_ANGLE    | VT_ARRAY<br>  VT_R4 | <p>Current robot position (each axis value). The unit is arbitrary. J type variable.</p> <p> <b>2.330</b></p> <p>For function specification, please refer to @HIGH_CURRENT_POSITION.</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                | √ | × |
| @HIGH_CURRENT_TRANS    | VT_ARRAY<br>  VT_R4 | <p>Current robot position expressed in T type.</p> <p> <b>2.330</b></p> <p>For function specification, please refer to @HIGH_CURRENT_POSITION.</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                      | √ | × |

## 4.3.3. Task class

Table 4-13 Task class system variable list

| Variable identifier | Data type | Explanation                                                                                                                                                                                                                                                                                                                                                                                                                                           | Attribute |     |
|---------------------|-----------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|-----------|-----|
|                     |           |                                                                                                                                                                                                                                                                                                                                                                                                                                                       | get       | put |
| @STATUS             | VT_I4     | State of task.<br>1: DORMANT<br>2: READY<br>3: RUN<br>4: WAIT<br>6: SUSPEND<br>0: NON_EXISTENT                                                                                                                                                                                                                                                                                                                                                        | √         | ×   |
| @PRIORITY           | VT_I4     | Priority of task.                                                                                                                                                                                                                                                                                                                                                                                                                                     | √         | ×   |
| @LINE_NO            | VT_I4     | Line – number of currently executing main program.                                                                                                                                                                                                                                                                                                                                                                                                    | √         | ×   |
| @CYCLE_TIME         | VT_I4     | One cycle execution time of task.                                                                                                                                                                                                                                                                                                                                                                                                                     | √         | ×   |
| @START              | VT_I4     | Start task. The meaning of the value is the same as the Mode argument of the CaoTask::Start method.<br>The mode is 1: one cycle execution, 2: continuous executes, 3: 1 step forward, <del>4: 1 step backward</del> , 5: resume all<br>(Note) If the value is set to 5 (resume all), then all suspended programs in the controller are resumed.<br> <b>2.330</b> | ×         | √   |
| @STOP               | VT_I4     | Stop task. The meaning of the value is the same as the Mode argument of the CaoTask::Stop method.<br>The mode is 0: default stop, 1: Instant stop, 2: step stop, 3: Cycle stop, 4: Initialization stop, 5: Suspend all<br>If an option is required, please use CaoTask::Stop method instead. Default stop (0) is the same as Instant stop (1).<br>(Note) If the value is set to 5 (resume all), then all programs in the controller are suspended.    | ×         | √   |

#### 4.3.4. File class

**Table 4–14 File class system variable list**

| Variable identifier | Data type | Explanation                                               | Attribute |     |
|---------------------|-----------|-----------------------------------------------------------|-----------|-----|
|                     |           |                                                           | get       | put |
| @ACTIVE             | VT_I4     | Active of file(compile flag).<br>0: Inactive<br>1: Active | √         | √   |
| @CRC                | VT_I4     | CRC32                                                     | √         | ×   |

## 5. Outline of robot operation command execution

 **2.330**

The execution of the robot motion commands of the CaoRobot class (Move, GoHome, Accelerate, Change, Speed, and Execute method) has been achieved in the following way. NetwoRC provider communicate with a PAC program RobSlave (RobSlave.pac) running on the robot controller, and the PAC program executes specified PAC command. Controller global variables I[0], T[0] and T[1] are used for communication between NetwoRC provider and RobSlave. I[0] is used to express the executing command status, e.g., running, completed, or error. T[0] is used to pass command and parameters from NetwoRC provider to RobSlave. T[1] is used to return value from RobSlave to NetwoRC provider.

Following diagram shows the execution procedure of robot motion command.

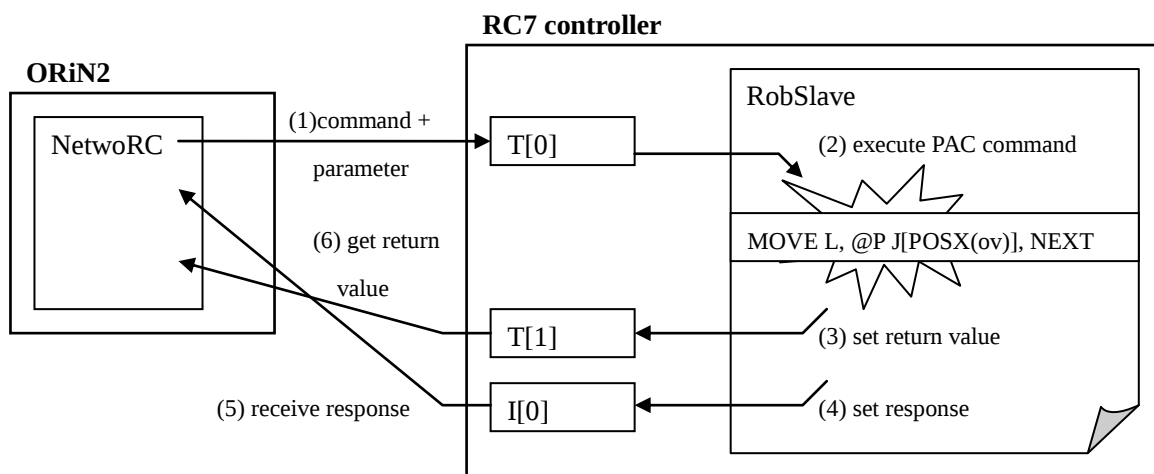


Figure 5-1 Execution procedure of robot motion command

### 【 attention 】

All global variables (I,F,D,V,P,J,T,S) from [0] to [9] have been reserved with the system.

Please do not access these variables in the user's program.

## 6. Tips

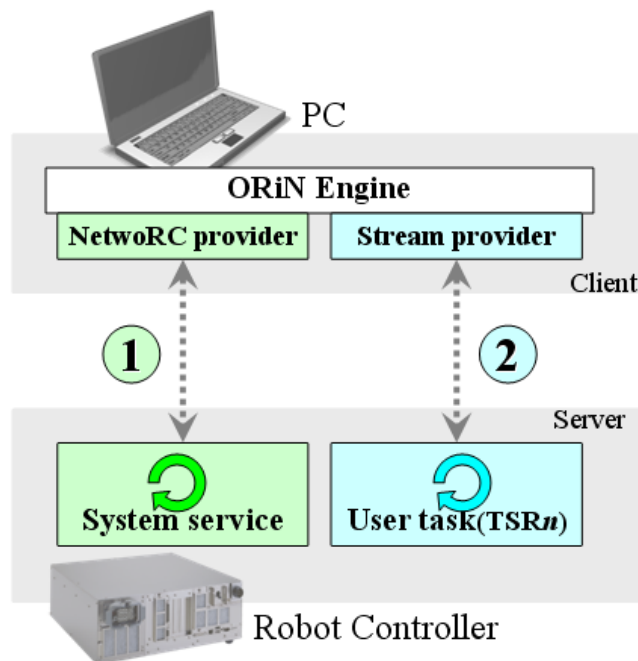
### 6.1. How to write data in an error state

NetwoRC controller rejects all writing data request (ex. Variable, I/O) when an error occurred because of safety reason. By using a supervisory task (PAC) in the controller, the limitation can be solved.

The supervisory tasks (TSR1, TSR2, ...) can write data during an error state, and those can be invoked at the startup of the controller. The procedure is as follows.

- (1) Enable a supervisory task
- (2) Make a supervisory task program which writes data when got notification from an external PC, and invoke the program.
- (3) Notify to the supervisory task from the PC.

The following figure shows an outline of the system using a supervisory task and NetwoRC provider simultaneously.



**Figure 6-1 Expanded system using a supervisory task (PAC)**

By combining Stream provider<sup>12</sup> and a supervisory task, it becomes possible to write data (ex. Variable, I/O) while an error occurred.

NetwoRC provider is much faster than this way, but it is useful for the manufacturing system recovery and so on (Table 6-1).

<sup>12</sup> Regarding Stream provider, please refer "Stream provider user's guide" in the ORiN2 SDK.

**Table 6-1 A comparison of communication methods**

| Method                                   | Speed       | Supervisory Task                           | Write data in an error state |
|------------------------------------------|-------------|--------------------------------------------|------------------------------|
| 1. NetwoRC provider<br>(ROBOTalk/UDP/IP) | <b>Fast</b> | <b>Not required</b><br>(System + RobSlave) | <b>Impossible</b>            |
| 2. Stream provider<br>(TCP/IP)           | <b>Slow</b> | <b>Required</b><br>(PAC program)           | <b>Possible</b>              |

For the details of a supervisory task, please refer the following manual.

DENSO ROBOT SETTING-UP MANUAL

Chapter 3 General Introduction to Operation Modes and Additional Functions

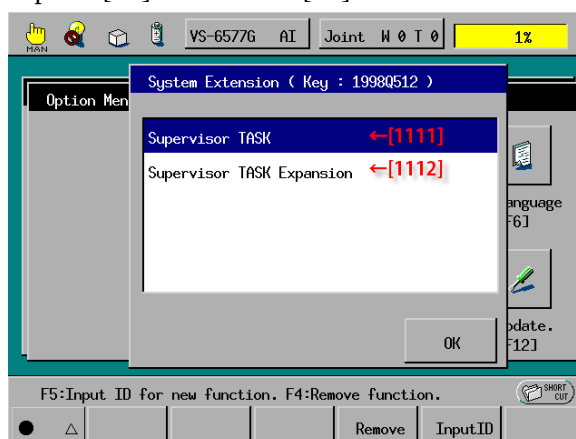
Supervisory Task (Software PLC)

### 6.1.1. Enable a supervisory task

To enable a supervisory task, the following steps are required.

(1) Add [1111] and [1112] options.

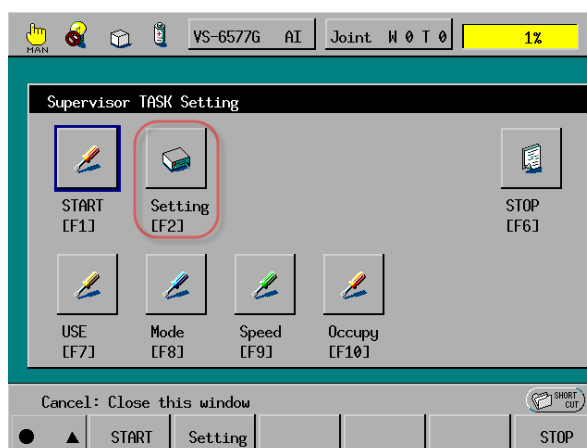
Top screen -> Set[F6] -> Options[F7] -> Extension[F8]



(2) Restart the controller.

(3) Enable a supervisory task.

Top screen -> SHIFT -> S-TASK[F2] -> Setting[F2]



(4) Restart the controller again.

### 6.1.2. Make a supervisory task

The following sample program writes I/O when it gets notification from an external PC. The controller is set as a server, and its input port number is #4, and its TCP port number is 5001.

#### List 6-1 TSR1.pac

```

PROGRAM TSR1
  Defint lval
  Defstr sval

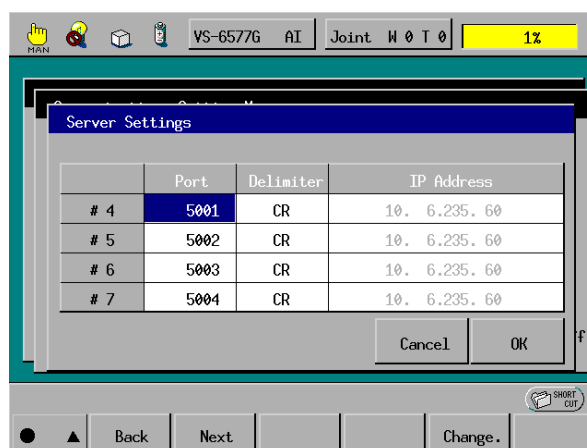
  Do ' Wait for a TCP connection
    com_state #4, lval
    If lval <> -1 Then Exit Do
    Delay 100
  Loop

  Do ' Wait for a command
    Input #4, sval ' #4 = TCP 5001 port
    lval = Val(sval) ' Covert character string to a number
    If lval>0 Then
      Set IO[lval] ' "128" -> IO[128] = ON
      Print #4, sval: " ON"
    Else
      Reset IO[-lval] ' "-128" -> IO[128] = OFF
      Print #4, sval: " OFF"
    End If
  Loop
END

```

[Controller setting]

Top screen -> Set[F6] -> Set Com.[F5] -> Server[F11]



### 6.1.3. Notify to a supervisory task from a PC

The following sample program using Stream provider notifies to a supervisory task. from a PC. The IP address and the port number should be changed according as set above.

#### List 6-2 Client.frm

```
Private eng As CaoEngine
Private WithEvents ctrl As CaoController

Private Sub Form_Load()
    Set eng = New CaoEngine

    ' Connect to NetwoRC controller as a client
    Set ctrl = eng.Workspaces(0).AddController("Client", _
        "CaoProv. DNWA. STREAM", _
        "", _
        "Conn=eth:192.168.0.1:5001")
End Sub

Private Sub Command1_Click()
    ' Send data
    ctrl.Execute "Send", text1.Text      ' Ex. "128" -> I0128=ON
End Sub

' Receive data
Private Sub ctrl_OnMessage(ppCaoMess As CAOLib.ICaoMessage)
    ' get data
    text2.Text = ppCaoMess.Value
End Sub
```

## Appendix A. POSEDATA type definition

In the NetwoRC provider, “POSEDATA” is defined so that the pose data type data and the vector type data of DENSO robot by VARIANT variable.

POSEDATA type (VARIANT)

|                              |                                                                       |
|------------------------------|-----------------------------------------------------------------------|
| VT_BSTR <sup>13</sup>        | "[<Pass>] [<Variable type>]<Index> [<ExJnt>]"                         |
|                              | or                                                                    |
|                              | "[<Pass>] [<Variable type>](<Element 1>,<Element 2>,...)<ExJnt>]"     |
| VT_R4 VT_ARRAY <sup>14</sup> | <Raw value> = (<Element 1:VT_R4>,<Element 2:VT_R4>,...) <sup>15</sup> |
| VT_VARIANT VT_ARRAY          | (<0:Value>[,<1:Variable type>[,<2:Path>[, <3:ExJnt>]]])               |
| <Value>                      | <Index:VT_R4>                                                         |
|                              | or                                                                    |
|                              | <Raw value:VT_R4 VT_ARRAY>                                            |
| <Variable type>              | P, T, J, V type (default=P)                                           |
| <Pass>                       | @P, @E, @0, @<value> (default=@0)                                     |
| <ExJnt>                      | <Extended-joints option:VT_VARIANT VT_ARRAY><br>(default=None)        |

<Pass> : @P, @E, @0, @<value>

| Mark    | @P   | @E   | @0   | @<数值:n> | None |
|---------|------|------|------|---------|------|
| VT_BSTR | "@P" | "@E" | "@0" | "@n"    | ""   |
| VT_I4   | -1   | -2   | 0    | n       | 0    |

<Variable type> : P type, T type, J type, V type

| Mark    | P   | T   | J   | V   | None |
|---------|-----|-----|-----|-----|------|
| VT_BSTR | "P" | "T" | "J" | "V" | ""   |
| VT_I4   | 0   | 1   | 2   | 3   | -1   |

<Index> : <value:VT\_R4>

<Element n> : <value:VT\_R4>

<Extended-joints> : (<EX or EXA>, (<Joint1:VT\_I4>, <Value1:VT\_R8>)[,

<sup>13</sup> In case of VT\_BSTR, more than one POSEDATA type separated by commas can be specified.

<sup>14</sup> Because <Variable type> and <Pass> cannot be specified, variable type is treated as P type and pass type is treated as @0 by default.

<sup>15</sup> Cannot specify the extended-joints option.

<option> (<Joint2>,<Value2>...)]

| 表記      | EX   | EXA   | なし |
|---------|------|-------|----|
| VT_BSTR | "EX" | "EXA" | "" |
| VT_I4   | 1    | 2     | 0  |

The following formats of PAC language can be indicated by POSEDATA type.

[<Pass start displacement >] <Pose:P,T,J type> [<ExJnt>] (C0-format)

[<Pass start displacement >] <Vector:V type> (C1-format)

[<Pass start displacement >] <Value> [<ExJnt>] (C2-format)

[<Pass start displacement >] (<Element1>,< Element 2>,...) [<ExJnt>] (C3-format)

## Appendix A.1. Examples

[<Pass start displacement >] <Pose:P,T,J type> [<ExJnt>] (C0-format)

### ex1. T200

|                                                              |                    |
|--------------------------------------------------------------|--------------------|
| String                                                       | "T200"             |
| VARIANT type array<br>(variable type specified by<br>string) | Array(200, "T") 16 |
| VARIANT type array<br>(variable type specified by<br>value)  | Array(200, 1)      |

### ex2. @P J100

|                                                                            |                       |
|----------------------------------------------------------------------------|-----------------------|
| String                                                                     | "@P J100"             |
| VARIANT type array<br>(variable type and pass type<br>specified by string) | Array(100, "J", "@P") |
| VARIANT type array<br>(variable type and pass type<br>specified by number) | Array(100, 2, -1)     |

### ex3. @E P(10.0, 10.5, 34.6, 0.0, 90.0, 0.0, -1.0)

|                                              |                                                                                                 |
|----------------------------------------------|-------------------------------------------------------------------------------------------------|
| String                                       | "@E P(10.0, 10.5, 34.6, 0.0, 90.0, 0.0, -1.0)"                                                  |
| VARIANT type array<br>(immediate value, with | Dim p(6) as Single<br>Dim vP as Variant<br>p(0) = 10.0 : p(1) = 10.5 : p(2) = 34.6 : p(3) = 0.0 |

<sup>16</sup> Array(...) is a function to return an array composed of the argument to the function. (Array function of VB6)

|                                                                                               |                                                                                                                                                                           |
|-----------------------------------------------------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| variable type and pass type specified by string)                                              | p(4) = 90.0 : p(5) = 0.0 : p(6) = -1.0<br>vP = p()<br>Array(vP, "P", "@E")                                                                                                |
| VARIANT type array<br>(immediate value, with variable name and pass type specified by number) | Dim p(6) as Single<br>Dim vP as Variant<br>p(0) = 10.0 : p(1) = 10.5 : p(2) = 34.6 : p(3) = 0.0<br>p(4) = 90.0 : p(5) = 0.0 : p(6) = -1.0<br>vP = p()<br>Array(vP, 0, -2) |

**ex4. @P J100 EXA((7, 30.5), (8, 90.5))**

|                                                                                    |                                                                     |
|------------------------------------------------------------------------------------|---------------------------------------------------------------------|
| String                                                                             | "@P J100 EXA((7, 30.5), (8, 90.5))"                                 |
| VARIANT type array<br>(variable type, pass type and aux. axis specified by string) | Array(100, "J", "@P", Array("EXA", Array(7, 30.5), Array(8, 90.5))) |
| VARIANT type array<br>(variable type, pass type and aux. axis specified by number) | Array(100, 2, -1, Array(2, Array(7, 30.5), Array(8, 90.5)))         |

|                                                          |
|----------------------------------------------------------|
| [<Pass start displacement >] <Vector:V type> (C1-format) |
|----------------------------------------------------------|

**ex1. @P V20**

|                                                                         |                      |
|-------------------------------------------------------------------------|----------------------|
| String                                                                  | "@P V20"             |
| VARIANT type array<br>(variable type and pass type specified by string) | Array(20, "V", "@P") |
| VARIANT type array<br>(variable type and pass type specified by number) | Array(20, 3, -1)     |

**ex2. @E V(0.0, 125.5, 50.0)**

|                                                                                               |                                                                                                                                         |
|-----------------------------------------------------------------------------------------------|-----------------------------------------------------------------------------------------------------------------------------------------|
| String                                                                                        | "@E V(0.0, 125.5, 50.0)"                                                                                                                |
| VARIANT type array<br>(immediate value, with variable type and pass type specified by string) | Dim v(2) as Single<br>Dim vV as Variant<br>v(0) = 0.0 : v(1) = 125.5 : v(2) = 50.0<br>vV = v()<br>Array(vV, "V", "@E")                  |
| VARIANT type array<br>(immediate value, with variable type and pass type specified by number) | Dim v(2) as Single<br>Dim vV as Variant<br>v(0) = 0.0 : v(1) = 125.5 : v(2) = 50.0<br>vV = v() ' = VT_R4   VT_ARRAY<br>Array(vV, 3, -2) |

|                                                |             |
|------------------------------------------------|-------------|
| [<Pass start displacement >] <Value> [<ExJnt>] | (C2-format) |
|------------------------------------------------|-------------|

**ex1. @P 1**

|                                                                            |                    |
|----------------------------------------------------------------------------|--------------------|
| String                                                                     | "@P 1"             |
| VARIANT type array<br>(variable type and pass type<br>specified by string) | Array(1, "", "@P") |
| VARIANT type array<br>(variable type and pass type<br>specified by number) | Array(1, -1, -1)   |

**ex2. @P 1.56**

|                                                                            |                       |
|----------------------------------------------------------------------------|-----------------------|
| String                                                                     | "@P 1.56"             |
| VARIANT type array<br>(variable type and pass type<br>specified by string) | Array(1.56, "", "@P") |
| VARIANT type array<br>(variable type and pass type<br>specified by number) | Array(1.56, -1, -1)   |

|                                                                      |             |
|----------------------------------------------------------------------|-------------|
| [<Pass start displacement >] (<Element1>,< Element 2>,...) [<ExJnt>] | (C3-format) |
|----------------------------------------------------------------------|-------------|

**ex1. @P (1, 30.0)**

|                                                                            |                                                                                                      |
|----------------------------------------------------------------------------|------------------------------------------------------------------------------------------------------|
| String                                                                     | "@P (1, 30.0)"                                                                                       |
| VARIANT type array<br>(variable type and pass type<br>specified by string) | Dim v(1) as Single<br>v(0) = 1 : v(1) = 30.0<br>Dim vV as Variant<br>vV = v()<br>Array(vV, "", "@P") |
| VARIANT type array<br>(variable type and pass type<br>specified by number) | Dim v(1) as Single<br>v(0) = 1 : v(1) = 30.0<br>Dim vV as Variant<br>vV = v()<br>Array(vV, -1, -1)   |

**Other examples****ex1. V1,V2,V3**

(Rotation plane for CaoRobot::Rotate())

|               |                                                    |
|---------------|----------------------------------------------------|
| String        | "V1, V2, V3"                                       |
| String array  | Array("V1", "V2", "V3")                            |
| VARIANT array | Array(Array(1, "V"), Array(2, "V"), Array(3, "V")) |

|                                      |                                              |
|--------------------------------------|----------------------------------------------|
| ( variable type specified by string) |                                              |
| VARIANT array                        | Array(Array(1, 3), Array(2, 3), Array(3, 3)) |
| ( variable type specified by number) |                                              |

**ex2. APPROACH P,P70, 60, NEXT**

(Approach command for CaoRobot::Execute(), without pass specification)

|                              |                                                                           |
|------------------------------|---------------------------------------------------------------------------|
| 2nd argument : string        | . Execute "APPROACH", Array(1, "P70", "60", "NEXT")                       |
| 3rd argument : string        |                                                                           |
| 2nd argument : VARIANT array | . Execute "APPROACH", Array(1, Array(70, "P"), Array(60, "", ""), "NEXT") |
| 3rd argument: VARIANT array  |                                                                           |

**ex3. APPROACH L,J(60.5,30.3,400,90),@100 70, NEXT**

(Approach command for CaoRobot::Execute(), without pass specification)

|                                                                                           |                                                                                                                                                                                                                 |
|-------------------------------------------------------------------------------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| 2nd argument : string                                                                     | . Execute "APPROACH", Array(2, "J(60.5, 30.3, 400, 90)", "@100 70", "NEXT")                                                                                                                                     |
| 3rd argument : string                                                                     |                                                                                                                                                                                                                 |
| 2nd argument : VARIANT array<br>(immediate value, with variable type specified by string) | Dim j(3) as Single<br>Dim vJ as Variant<br>j(0) = 60.5 : j(1) = 30.3 : j(2) = 400 : j(3) = 90<br>vJ = j() ' = VT_R4   VT_ARRAY<br>. Execute "APPROACH", Array(2, Array(vJ, "J"), Array(70, "", "@100"), "NEXT") |
| 3rd argument : VARIANT array<br>(immediate value, with variable type specified by string) |                                                                                                                                                                                                                 |
| 2nd argument : VARIANT array<br>(immediate value, with variable type specified by string) | Dim j(3) as Single<br>Dim vJ as Variant<br>j(0) = 60.5 : j(1) = 30.3 : j(2) = 400 : j(3) = 90<br>vJ = j() ' = VT_R4   VT_ARRAY<br>. Execute "APPROACH", Array(2, Array(vJ, "J"), Array(70, -1, 100), "NEXT")    |
| 3rd argument : VARIANT array<br>(immediate value, with variable type specified by number) |                                                                                                                                                                                                                 |

**【 attention 】**

When the value is immediately specified directly by POSEDATA type by VT\_R4|VT\_ARRAY form, it becomes P type and @0 by default. Therefore, data other than P type cannot be specified directly by the VT\_R4|VT\_ARRAY form. In this case, please specify the variable type of the data by the VT\_VARIANT|VT\_ARRAY form or VT\_BSTR form.

Please note that the following codes do not make sense.

‘[PAC] MOVE P, J100

Dim vJ as Variant

vJ=CaoCtrl.Variables("J100").Value   ‘VT\_R4|VT\_ARRAY

Robot.Move 1, vJ                   ‘= MOVE P, P(<j1>,<j2>,<j3>,...) NG!!

The correct code is as follows.

Robot.Move 1, Array(vJ,"J")           ‘=MOVE P, J(<j1>,<j2>,<j3>,...) OK

## Appendix B. PAC Commands supported by NetwoRC provider



Table 6–2 List of PAC Commands

| Group          | Commands       | Availability |
|----------------|----------------|--------------|
| Motion Control |                |              |
|                | APPROACH       | √            |
|                | DEPART         | √            |
|                | DRAW           | √            |
|                | DRIVE          | √            |
|                | DRIVEA         | √            |
|                | HOME           | ×            |
|                | GOHOME         | ×            |
|                | MOVE           | √            |
|                | ROTATE         | √            |
|                | ROTATEH        | √            |
|                | CURJNT         | √            |
|                | CURPOS         | √            |
|                | CURTRN         | √            |
|                | CUREXJ         | ×            |
|                | DESTJNT        | ×            |
|                | DESTPOS        | ×            |
|                | DESTTRN        | ×            |
|                | DESTEXJ        | ×            |
|                | ARRIVE         | √            |
|                | POSLR          | √            |
|                | SETSPLINEPOINT | √            |
|                | CLRSPLINEPOINT | √            |
|                | GETSPLINEPOINT | √            |
|                | FIGAPRL        | √            |
|                | FIGAPRP        | √            |
| Stop Control   |                |              |
|                | HOLD           | ×            |

|                     |                  |   |
|---------------------|------------------|---|
|                     | HALT             | × |
|                     | INTERRUPT ON/OFF | √ |
| Speed Control       |                  |   |
|                     | SPEED            | √ |
|                     | JSPEED           | √ |
|                     | ACCEL            | √ |
|                     | JACCEL           | √ |
|                     | DECEL            | √ |
|                     | JDECEL           | √ |
|                     | CURACC           | √ |
|                     | CURJACC          | √ |
|                     | CURDEC           | √ |
|                     | CURJDEC          | √ |
|                     | CURJSPD          | √ |
|                     | CURSPD           | √ |
|                     | CUREXTACC        | √ |
|                     | CUREXTDEC        | √ |
|                     | CUREXTSPD        | √ |
|                     | EXTSPEED         | √ |
|                     | CHANGETOOL       | √ |
|                     | CHANGework       | √ |
|                     | CURTOOL          | √ |
|                     | CURWORK          | √ |
| Interference Check  |                  |   |
|                     | SETAREA          | √ |
|                     | RESETAREA        | √ |
| Internal Servo Data |                  |   |
|                     | GetSrvData       | √ |
|                     | GetJntData       | √ |

|                    |                     |   |
|--------------------|---------------------|---|
|                    | GetSrvState         | √ |
| Motor Power        |                     |   |
|                    | MOTOR {ON OFF}      | √ |
| Particular Control |                     |   |
|                    | ST_aspACLD          | √ |
|                    | ST_aspChange        | √ |
|                    | ST_SetGravity       | √ |
|                    | ST_ResetGravity     | √ |
|                    | ST_SetGrvOffset     | √ |
|                    | ST_ResetGrvOffset   | √ |
|                    | ST_SetCurLmt        | √ |
|                    | ST_ResetCurLmt      | √ |
|                    | ST_SetEralw         | √ |
|                    | ST_ResetEralw       | √ |
|                    | ST_OnSrvLock        | √ |
|                    | ST_OffSrvLoc        | √ |
|                    | ST_SetCompControl   | √ |
|                    | ST_SetCompFControl  | √ |
|                    | ST_ResetCompControl | √ |
|                    | ST_SetFrcCoord      | √ |
|                    | ST_SetFrcLimit      | √ |
|                    | ST_ResetFrcLimit    | √ |
|                    | ST_SetCompRate      | √ |
|                    | ST_ResetCompRate    | √ |
|                    | ST_SetFrcAssist     | √ |
|                    | ST_ResetFrcAssist   | √ |
|                    | ST_SetCompJLimit    | √ |
|                    | ST_ResetCompJLimit  | √ |
|                    | ST_SetCompVMode     | √ |
|                    | ST_ResetCompVMode   | √ |
|                    | ST_SetCompEralw     | √ |
|                    | ST_ResetCompEralw   | √ |
|                    | ST_SetDampRate      | √ |
|                    | ST_ResetDampRate    | √ |
|                    | ST_SetZBalance      | √ |

|                               |                     |   |
|-------------------------------|---------------------|---|
|                               | ST_ResetZBalance    | √ |
| Pose Data Type Transformation |                     |   |
|                               | J2P                 | √ |
|                               | J2T                 | √ |
|                               | P2J                 | √ |
|                               | P2T                 | √ |
|                               | T2J                 | √ |
|                               | T2P                 | √ |
|                               | TINV                | √ |
|                               | NORMTRN             | √ |
| Conveyer Tracking             |                     |   |
|                               | TRACKDATAINITIALIZE | √ |
|                               | TRACKDATASET        | √ |
|                               | TRACKDATAGET        | √ |
|                               | TRACKDATAINFO       | √ |
|                               | TRACKDATANUM        | √ |
|                               | CURTRACKPOS         | √ |
|                               | CURTRACKSPD         | √ |
|                               | WAITTRACKMOVE       | √ |
|                               | CALCWORKPOS         | √ |
|                               | CURTRACKPOSEX       | √ |
|                               | WAITTRACKMOVEEX     | √ |
|                               | SETTRACKMOVE        | √ |
|                               | RESETTRACKMOVE      | √ |
|                               | CONVCAL             | × |
|                               | CALCCAMCALPOS       | × |
|                               | CALCIOTEACHPOS      | × |
|                               | SetTrackStartArea   | √ |
|                               | CalcConvPos         | × |
|                               | SetConvLowVelErr    | × |
|                               | CalcConvVec         | × |
|                               | SortTrackData       | × |
|                               | SortTrackAllData    | × |
| Other                         |                     |   |
|                               | MotionSkip          | √ |

---

|  |                 |   |
|--|-----------------|---|
|  | MotionComp      | √ |
|  | XdWaitSpline    | √ |
|  | DELAY           | √ |
|  | SYSSTATE        | √ |
|  | ClearSrvMonitor | √ |
|  | StartSrvMonitor | √ |
|  | StopSrvMonitor  | √ |

## Appendix C. Trouble-Shooting

### Appendix C.1. I cannot connect with a robot controller...

| Check                                                                                                               | Action                                                                                                                                                                                                                                 |
|---------------------------------------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| <b>■ Robot controller side</b>                                                                                      |                                                                                                                                                                                                                                        |
| <input type="checkbox"/> Is the NetwoRC ROM version higher than V2.330?                                             | If version is below v.2330, please update controller ROM Image to v2.330 or above.                                                                                                                                                     |
| <input type="checkbox"/> Is the cable, RS232C or Ethernet cable connected properly?                                 | Ensure that the cable is not loose on the connector.                                                                                                                                                                                   |
| <input type="checkbox"/> Is the type of cable such as Straight and Cross correct?                                   | Check the cable.                                                                                                                                                                                                                       |
| <input type="checkbox"/> In case of Ethernet, is the address correctly set?                                         | Check the address settings.                                                                                                                                                                                                            |
| <input type="checkbox"/> In case of the ethernet connection over the segment, is the default gateway correctly set? | Make sure that the Controller IP address in the COM settings is the same between the application and the controller. Make sure that the IP address of the client PC and the IP address of the ext. run on the controller are the same. |
| <input type="checkbox"/> In case of RS232c, is the communication parameter correctly set?                           | Check the parameters of RS232c.                                                                                                                                                                                                        |
| <input type="checkbox"/> Is the communication permission on the communication menu correctly set?                   | Check the communication permission. (see 2.2.1)                                                                                                                                                                                        |
| <input type="checkbox"/> Is the ORiN extension set?                                                                 | Add the ORiN option. (see 2.2.1)                                                                                                                                                                                                       |
| <b>■ PC side</b>                                                                                                    |                                                                                                                                                                                                                                        |
| <input type="checkbox"/> Is the Windows version correct? (Windows 2000, Windwos XP)                                 | Check the version.                                                                                                                                                                                                                     |
| <input type="checkbox"/> In case of RS232c, is another application program such as HyperTerminal running?           | Terminate the application.                                                                                                                                                                                                             |
| <input type="checkbox"/> Does RobMaster work properly?                                                              | Execute RobMaster.exe. The RobMaster application should be running on Windows.                                                                                                                                                         |
| <input type="checkbox"/> Are the parameters of the AddController() function correctly set?                          | Check the arguments of the AddController function. (see 4.2.1)                                                                                                                                                                         |
| <input type="checkbox"/> Is the version of ORiN up to v.2.0.3?                                                      | Verify ORiN2 version by executing CAOConfig. Select Help and then select Version.                                                                                                                                                      |

**Appendix C.2. I cannot access variables of a robot controller...**

| Check                                                                                                 | Action                                        |
|-------------------------------------------------------------------------------------------------------|-----------------------------------------------|
| <b>■ Robot controller side</b>                                                                        |                                               |
| <input type="checkbox"/> Is the communication permission correctly set? ("Read/Write" or "Read-only") | Check the communication settings. (see 2.2.1) |
| <input type="checkbox"/> Is any edit dialogue displayed in the teach pendant?                         | Close the dialogue.                           |
| <input type="checkbox"/> Is any error message displayed in the teach pendant?                         | Clear the error.                              |
| <b>■ PC side</b>                                                                                      |                                               |
| <input type="checkbox"/> Is the variable name correctly set?                                          | Check the variable name.                      |
| <input type="checkbox"/> In case of writing, is not the variable read-only?                           | Check the variable and I/O attribute.         |
| <input type="checkbox"/> Is the range of index correctly specified?                                   | Check the range.                              |
| <input type="checkbox"/> Do the written value and type meet the specification of the variable?        | Check the specifications.                     |

**Appendix C.3. I cannot move a robot...**

| Check                                                                                                         | Action                                             |
|---------------------------------------------------------------------------------------------------------------|----------------------------------------------------|
| <b>■ Robot controller side</b>                                                                                |                                                    |
| <input type="checkbox"/> Is the "Executable token" for a robot correctly set? (ANSI: Single point of control) | Check the settings. (see 2.4.2 for ANSI type)      |
| <input type="checkbox"/> Is the "RobSlave" program running?                                                   | Run the "RobSlave" program. (see 2.6)              |
| <input type="checkbox"/> Is the robot in the executable state?                                                | Check the condition. (see 2.2.1)                   |
| <input type="checkbox"/> Does RobSlave.pac match the version of "NetwoRC Provider"?                           | Use the modules included in the same ORiN Package. |
| <b>■ PC side</b>                                                                                              |                                                    |
| <input type="checkbox"/> Are the command names and parameters correctly specified?                            | Check the command (function) specification.        |

## Appendix D. Controllers supported by NetwoRC provider

Table 6–3 List of supported Controllers

| Class         | Property, Method, Event | R/W | RC5                   |                       | RC7                   |                       | Description |  |
|---------------|-------------------------|-----|-----------------------|-----------------------|-----------------------|-----------------------|-------------|--|
|               |                         |     | Less<br>than<br>1.998 | 1.998<br>or<br>higher | Less<br>than<br>2.330 | 2.330<br>or<br>higher |             |  |
| CaoController | Attribute               | P   | R                     | -                     | √                     | -                     | √           |  |
|               | CommandNames            | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Commands                | P   | R                     | -                     | √                     | -                     | √           |  |
|               | ExtensionNames          | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Extensions              | P   | R                     | -                     | √                     | -                     | √           |  |
|               | FileNames               | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Files                   | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Help                    | P   | R                     | -                     | √                     | -                     | √           |  |
|               | ID                      | P   | R/W                   | -                     | √                     | -                     | √           |  |
|               | Index                   | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Name                    | P   | R                     | -                     | √                     | -                     | √           |  |
|               | RobotNames              | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Robots                  | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Tag                     | P   | R/W                   | -                     | √                     | -                     | √           |  |
|               | TaskNames               | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Tasks                   | P   | R                     | -                     | √                     | -                     | √           |  |
|               | VariableNames           | P   | R                     | -                     | √                     | -                     | √           |  |
|               | Variables               | P   | R                     | -                     | √                     | -                     | √           |  |
|               | AddCommand              | M   | S                     | -                     | √                     | -                     | √           |  |
|               | AddExtension            | M   | S                     | -                     | √                     | -                     | √           |  |
|               | AddFile                 | M   | S                     | -                     | √                     | -                     | √           |  |
|               | AddRobot                | M   | S                     | -                     | √                     | -                     | √           |  |
|               | AddTask                 | M   | S                     | -                     | √                     | -                     | √           |  |
|               | AddVariable             | M   | S                     | -                     | √                     | -                     | √           |  |
|               | Execute                 | M   | S                     | -                     | √                     | -                     | √           |  |
|               | GetMessage              | M   | R                     | -                     | √                     | -                     | √           |  |
|               | OnMessage               | E   | R                     | -                     | √                     | -                     | √           |  |

|             |                  |   |     |   |   |   |   |
|-------------|------------------|---|-----|---|---|---|---|
|             |                  |   |     |   | - |   |   |
| CaoVariable | Attribute        | P | R   | - | √ | - | √ |
|             | DateTime         | P | R   | - | √ | - | √ |
|             | Help             | P | R   | - | √ | - | √ |
|             | ID               | P | R/W | - | √ | - | √ |
|             | Index            | P | R   | - | √ | - | √ |
|             | Microsecond      | P | R   | - | √ | - | √ |
|             | Name             | P | R   | - | √ | - | √ |
|             | Tag              | P | R/W | - | √ | - | √ |
|             | Value            | P | R/W | - | √ | - | √ |
|             |                  |   |     |   |   |   |   |
| CaoFile     | Attribute        | P | R   | - | √ | - | √ |
|             | DateCreated      | P | R   | - | √ | - | √ |
|             | DateLastAccessed | P | R   | - | √ | - | √ |
|             | DateLastModified | P | R   | - | √ | - | √ |
|             | FileNames        | P | R   | - | √ | - | √ |
|             | Files            | P | R   | - | √ | - | √ |
|             | Help             | P | R   | - | √ | - | √ |
|             | ID               | P | R/W | - | √ | - | √ |
|             | Index            | P | R   | - | √ | - | √ |
|             | Name             | P | R   | - | √ | - | √ |
|             | Path             | P | R   | - | √ | - | √ |
|             | Size             | P | R   | - | √ | - | √ |
|             | Tag              | P | R/W | - | √ | - | √ |
|             | Type             | P | R   | - | √ | - | √ |
|             | Value            | P | R/W | - | √ | - | √ |
|             | VariableNames    | P | R   | - | √ | - | √ |
|             | Variables        | P | R   | - | √ | - | √ |
|             | AddFile          | M | S   | - | √ | - | √ |
|             | AddVariable      | M | S   | - | √ | - | √ |
|             | Copy             | M | W   | - | √ | - | √ |
|             | Delete           | M | W   | - | √ | - | √ |
|             | Execute          | M | S   | - | √ | - | √ |
|             | Move             | M | W   | - | √ | - | √ |
|             | Run              | M | W   | - | - | - | - |

|          |               |   |     |   |   |   |                  |
|----------|---------------|---|-----|---|---|---|------------------|
|          |               |   |     |   |   |   |                  |
| CaoTask  | Attribute     | P | R   | - | √ | - | √                |
|          | FileName      | P | R   | - | √ | - | √                |
|          | Help          | P | R   | - | √ | - | √                |
|          | ID            | P | R/W | - | √ | - | √                |
|          | Index         | P | R   | - | √ | - | √                |
|          | Name          | P | R   | - | √ | - | √                |
|          | Tag           | P | R/W | - | √ | - | √                |
|          | VariableNames | P | R   | - | √ | - | √                |
|          | Variables     | P | R   | - | √ | - | √                |
|          | AddVariable   | M | S   | - | √ | - | √                |
|          | Delete        | M | W   | - | √ | - | √                |
|          | Execute       | M | S   | - | √ | - | √                |
|          | Start         | M | W   | - | - | - | √                |
|          | Stop          | M | W   | - | √ | - | √                |
|          |               |   |     |   |   |   |                  |
| CaoRobot | Attribute     | P | R   | - | √ | - | √                |
|          | Help          | P | R   | - | √ | - | √                |
|          | ID            | P | R/W | - | √ | - | √                |
|          | Index         | P | R   | - | √ | - | √                |
|          | Name          | P | R   | - | √ | - | √                |
|          | Tag           | P | R/W | - | √ | - | √                |
|          | VariableNames | P | R   | - | √ | - | √                |
|          | Variables     | P | R   | - | √ | - | √                |
|          | Accelerate    | M | W   | - | - | - | √                |
|          | AddVariable   | M | S   | - | √ | - | √                |
|          | Change        | M | W   | - | - | - | √                |
|          | Chuck         | M | W   | - | - | - | -                |
|          | Drive         | M | W   | - | - | - | -                |
|          |               |   |     |   |   |   | See<br>“Execute” |
|          | Execute       | M | S   | - | - | - | √                |
|          | GoHome        | M | W   | - | - | - | -                |
|          | Hold          | M | W   | - | - | - | √                |
|          | Halt          | M | W   | - | - | - | √                |
|          | Move          | M | W   | - | - | - | √                |

|              |               |   |     |   |   |   |   |  |
|--------------|---------------|---|-----|---|---|---|---|--|
|              | Rotate        | M | W   | - | - | - | √ |  |
|              | Speed         | M | W   | - | - | - | √ |  |
|              | Unchuck       | M | W   | - | - | - | - |  |
|              | Unhold        | M | W   | - | - | - | - |  |
|              |               |   |     |   |   |   |   |  |
| CaoCommand   | Attribute     | P | R   | - | √ | - | √ |  |
|              | Help          | P | R   | - | √ | - | √ |  |
|              | ID            | P | R/W | - | √ | - | √ |  |
|              | Index         | P | R   | - | √ | - | √ |  |
|              | Name          | P | R   | - | √ | - | √ |  |
|              | Parameters    | P | R/W | - | √ | - | √ |  |
|              | Result        | P | R   | - | √ | - | √ |  |
|              | State         | P | R   | - | √ | - | √ |  |
|              | Tag           | P | R/W | - | √ | - | √ |  |
|              | Timeout       | P | R/W | - | √ | - | √ |  |
|              | Cancel        | M | S   | - | √ | - | √ |  |
|              | Execute       | M | S   | - | √ | - | √ |  |
|              |               |   |     |   |   |   |   |  |
| CaoExtension | Attribute     | P | R   | - | √ | - | √ |  |
|              | Help          | P | R   | - | √ | - | √ |  |
|              | ID            | P | R/W | - | √ | - | √ |  |
|              | Index         | P | R   | - | √ | - | √ |  |
|              | Name          | P | R   | - | √ | - | √ |  |
|              | Tag           | P | R/W | - | √ | - | √ |  |
|              | VariableNames | P | R   | - | √ | - | √ |  |
|              | Variables     | P | R   | - | √ | - | √ |  |
|              | AddVariable   | M | S   | - | √ | - | √ |  |
|              | Execute       | M | S   | - | √ | - | √ |  |
|              |               |   |     |   |   |   |   |  |
| CaoMessage   | DateTime      | P | R   | - | √ | - | √ |  |
|              | Description   | P | R   | - | √ | - | √ |  |
|              | Destination   | P | R   | - | √ | - | √ |  |
|              | Number        | P | R   | - | √ | - | √ |  |
|              | SerialNumber  | P | R   | - | √ | - | √ |  |
|              | Source        | P | R   | - | √ | - | √ |  |

|                 |                                      |   |                                         |   |   |   |   |  |
|-----------------|--------------------------------------|---|-----------------------------------------|---|---|---|---|--|
|                 | Value                                | P | R                                       | - | √ | - | √ |  |
|                 | Clear                                | M | W                                       | - | √ | - | √ |  |
|                 | Reply                                | M | W                                       | - | √ | - | √ |  |
|                 |                                      |   |                                         |   |   |   |   |  |
| Meaning of sign | M: Method<br>P: Property<br>E: Event |   | R: Read<br>W: Write<br>S: Specification |   |   |   |   |  |

## Appendix E. Error code of NetwoRC provider

The structure of the NetwoRC provider error code is HRESULT format. Please refer to the following URL for the HRESULT structure.

<<http://msdn2.microsoft.com/en-us/library/bb401631.aspx>>

There are two kinds of error codes in the provider. One is "Standard error codes" defined by Microsoft Windows, and the other is "Custom error codes" defined by NetwoRC provider. The standard error is the global error defined in Winerror.h. The custom error is the local error defined in the NetwoRC provider. The table of the error codes is shown as follows.

**Table 6-4 Error code of NetwoRC provider**

| Number                          | Macro name                | Description                                                                                  |
|---------------------------------|---------------------------|----------------------------------------------------------------------------------------------|
| <b>Standard Error (excerpt)</b> |                           |                                                                                              |
| 0x00000000                      | S_OK                      | No error occurred                                                                            |
| 0x00000001                      | S_FALSE                   | No error occurred, but the command was not finished properly.                                |
| 0x8000FFFF                      | E_UNEXPECTED              | Catastrophic failure                                                                         |
| 0x80004001                      | E_NOTIMPL                 | Not implemented                                                                              |
| 0x8007000E                      | E_OUTOFMEMORY             | Ran out of memory                                                                            |
| 0x80070057                      | E_INVALIDARG              | One or more arguments are invalid                                                            |
| 0x80004005                      | E_FAIL                    | Unspecified error                                                                            |
| <b>Custom Error</b>             |                           |                                                                                              |
| 0x80000801                      | E_CAOP_NO_ROBSLAVE        | RobSlave program does not exist in the robot controller.                                     |
| 0x80000802                      | E_CAOP_ROBSLAVE_NOT_READY | RobSlave program in the robot controller is not running.                                     |
| 0x80000803                      | E_CAOP_ROBSLAVE_CRC_ERROR | RobSlave program CRC error.                                                                  |
| 0x80000804                      | E_CAOP_ILLEGAL_CTRLVER    | Illegal robot controller version.                                                            |
| 0x80000805                      | E_CAOP_NO_EXECUTE_TOKEN   | No executable token.                                                                         |
| 0x80000806                      | E_CAOP_ILLEGAL_ROBSLAVE   | Illegal RobSlave version.                                                                    |
| 0x80000807                      | E_CAOP_NO_LICENSE         | The count of connections is over the possible number. Please purchase an additional license. |
| 0x80000900                      | E_TIMEOUT                 | Timeout occurred                                                                             |
| 0x80010900                      | E_SEND_NAK                | NAK occurred                                                                                 |

|            |                     |                       |
|------------|---------------------|-----------------------|
| 0x80010902 | E_REJECTED          | Reject occurred       |
| 0x80010903 | E_ABNORMAL_R_PACKET | Receive packet broken |
| 0x80010904 | E_ABNORMAL_S_PACKET | Send packet broken    |

## Appendix F. Non-Stop Motion Calculator - Trajectory

### Generator Command for Non Stop Inspection

#### Appendix F.1. Parameter

Following is details of <Position> parameter and <Area> parameter of GenerateNonStopPath command.

<Position: VT\_VARIANT | VT\_ARRAY> =

<X: VT\_R4>,  
 <Y: VT\_R4>,  
 <Z: VT\_R4>,  
 <RX: VT\_R4>,  
 <RY: VT\_R4>,  
 <RZ: VT\_R4>,  
 <Fig: VT\_I4>,  
 <J7: VT\_R4>,  
 <J8: VT\_R4>,  
 <Motion Velocity : VT\_R4>=(0.0~1.0),  
 <Motion Pattern: VT\_I4> = (0: @P, 1: @0, 2: @E),  
 <Tool Number: VT\_I4>

<Area: VT\_R4 | VT\_ARRAY> =

<Area Size X: VT\_R4>,  
 <Area Size Y: VT\_R4>,  
 <Area Size Z: VT\_R4>,  
 <Area Angle: VT\_R4>,  
 <Area Size J7: VT\_R4>,  
 <Area Size J8: VT\_R4>

#### Appendix F.2. Error Codes

The following table shows error codes of GenerateNonStopPath Command, which is defined in the provider.

| Error No.  | Macro Name       | Meaning                                 |
|------------|------------------|-----------------------------------------|
| 0x800120** | ERR_ORG_P2J_CONV | Conversion Error from Position to Joint |

|            |                        |                                                               |
|------------|------------------------|---------------------------------------------------------------|
|            |                        | (Teaching Data)                                               |
| 0x800121** | ERR_ORG_SOFT_LIMIT     | Software limit Error (Teaching Data)                          |
| 0x800122** | ERR_ECH_SPD_RATE       | Out of Speed Rate Range                                       |
| 0x800123** | ERR_GEN_P2J_CONV       | Conversion Error from Position to Joint<br><br>(Revised Data) |
| 0x800124** | ERR_GEN_SOFT_LIMIT     | Software limit Error (Revised Data)                           |
| 0x800125** | ERR_GEN_IMPOSSIBLE     | Revision operation convergence is<br><br>impossible           |
| 0x800126** | ERR_TOO_NEAR_POINT     | Too near teaching points (Position and<br><br>Posture)        |
| 0x800127** | ERR_SPEED_ZERO         | Zero Speed definition                                         |
| 0x800128** | ERR_INVALID_AREA_INFO  | Invalid Area Data (Teaching Data)                             |
| 0x80012A0* | ERR_INVALID_JOINTFLG   | Joint Flag must be set as “limited rotation”.                 |
| 0x80012F00 | ERR_SPEED_RATE         | Out of total speed rate range                                 |
| 0x80012F01 | ERR_GEN_COEF           | Out of Coefficients Range                                     |
| 0x80012F02 | ERR_PASS_GEN           | Trajectory Pass Generation fail                               |
| 0x80012F03 | ERR_MEMORY_TOO_SMALL   | Low Memory                                                    |
| 0x80012F04 | ERR_ARMDNTLL_LOAD_FAIL | ArmNT.dll Load fail                                           |
| 0x80012F05 | ERR_DIVISION_BY_ZERO   | Division by Zero                                              |
| 0x80012F06 | ERR_UNESTB_ARMCNF      | ArmCnf is unsetted                                            |
| 0x80012F07 | ERR_UNESTB_SPDCNF      | SpdCnf is unsetted                                            |
| 0x80012F08 | ERR_UNESTB_SRVCNF      | SrvCnf is unsetted                                            |
| 0x80012F09 | ERR_MEMORY_LEAK        | Memory Leak                                                   |
| 0x80012F0A | ERR_OUT_OF_DATA_NUM    | Out of Data Number                                            |
| 0x80012F10 | ERR_INVALID_TOOL_DATA  | Invalid Tool Data                                             |

|            |                     |                    |
|------------|---------------------|--------------------|
| 0x80012F50 | ERR_OUT_OF_TOOL_NUM | Out of Tool Number |
|------------|---------------------|--------------------|

Error Code: 0x80012000~0x80012800

The symbol of “\*\*\*” indicates the error occurred position number. The value is “the error occurred position number + 1”.

Error Code: 0x80012A0\*

The symbol of “\*” indicates the number of the axis which is set as “unlimited rotation”.

### Appendix F.3. Restrictions

Restrictions of GenerateNonStopPath Command are as follows:

- Max. Number of Teaching Points = 200
- Available for 6-axis robot only
- Area size for additional axis should be assigned in [degree] (for rotational axis) or [mm] (for linear axis) according to the axis setting.
- Unavailable for Unlimited rotation of the extra-joint
- Unavailable when Auto Speed and Auto Acceleration mode is used
- Payload setting is restricted to the unit of 1,000g.

### Appendix F.4. Sample Program

The following sample program is described in CaoScript. The following sample teaching data is for VS-6577G-BA robot. Assign appropriate IP Address for the target controller. This sample assumes the target controller IP address is 10.6.235.72.

| Sample | NonStopPath.vbs                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                  |
|--------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
|        | <pre> ' Generate NonStopPath Const RC_ADDRESS = "10. 6. 235. 72"  Sub Main   Dim rc   Dim vntTeachPos()   Dim vntAreaInfo()   Dim vntMovePos   Dim vntParam   Dim lIndex    dbg.ClearLog    set rc = cao.AddController("RC", "GaoProv.DENSO.NetwoRC", "", "conn = eth:" &amp; RC_ADDRESS)   ' -----   ' Initialize NonStopPath Library   ' -----   call rc.Execute("InitNonStopPathLib")    ' GenerateNonStopPath Command Parameter (Pos, Area, Size, SpdRate, Coef)   ' Pos : TeachPoint Data (x, y, z, rx, ry, rz, fig, J7, J8, SpdRate, attr, ToolNum) </pre> |

```

redim vntTeachPos(7)

vntTeachPos(0) = Array(300.0, 100.0, 600.0, 180.0, 0.0, 180.0, 5, 0.0, 0.0, 100 * 0.01, 1, 0)
vntTeachPos(1) = Array(300.0, 91.0, 600.0, 180.0, 0.0, -180.0, 5, 0.0, 0.0, 100 * 0.01, 0, 0)
vntTeachPos(2) = Array(310.0, 30.0, 600.0, 180.0, 0.0, -180.0, 5, 0.0, 0.0, 100 * 0.01, 1, 0)
vntTeachPos(3) = Array(315.5, 24.5, 600.0, 180.0, 0.0, -180.0, 5, 0.0, 0.0, 100 * 0.01, 0, 0)
vntTeachPos(4) = Array(300.0, 10.0, 600.0, 180.0, 0.0, 173.0, 5, 0.0, 0.0, 100 * 0.01, 1, 0)
vntTeachPos(5) = Array(300.0, 10.0, 600.0, 180.0, 0.0, 176.0, 5, 0.0, 0.0, 100 * 0.01, 0, 0)
vntTeachPos(6) = Array(300.0, 10.0, 600.0, 180.0, 0.0, 171.0, 5, 0.0, 0.0, 100 * 0.01, 0, 0)
vntTeachPos(7) = Array(300.0, 10.0, 600.0, 180.0, 0.0, -180.0, 5, 0.0, 0.0, 100 * 0.01, 1, 0)

' Area : Area Info (x, y, z, angle, J7, J8)
redim vntAreaInfo(7)

vntAreaInfo(0) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(1) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(2) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(3) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(4) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(5) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(6) = Array(4, 4, 4, 4, 0, 0)
vntAreaInfo(7) = Array(4, 4, 4, 4, 0, 0)

dbg. Output "Teach Points"
for IIndex = 0 to Ubound(vntTeachPos)
    dbg. Output IIndex & " : " & dat.BstrFromVariant(vntTeachPos(IIndex))
next

' -----
' Generate NonStopPath
' -----

vntMovePos = rc.Execute("GenerateNonStopPath", Array(vntTeachPos, vntAreaInfo,
Ubound(vntTeachPos) + 1, 100.0 * 0.01, 0.7, 1))

dbg. Output "Move Points"
for IIndex = 0 to Ubound(vntMovePos)
    dbg. Output IIndex & " : " & dat.BstrFromVariant(vntMovePos(IIndex))
next
End Sub

```

## Appendix F.5. Workaround at the time of the Adjustment Failure (Error Code:0x800123xx)

The GenerateNonStopPath command fails when the revised angle is out of maximum adjustment angle range. If the failure occurs and error code 0x800123xx (xx represents teaching position number) is shown, change the teaching position, or adjust parameters for the selected Adjustment Method as shown in below.

- In case of Synchronous motion with Extended-Joint (default)

Adjust the following parameters in cOrbitGenSync.ini (in Bin folder of NetwoRC Provider)

| Parameter                     | Overtime                                                             | Input Limitation |
|-------------------------------|----------------------------------------------------------------------|------------------|
| FIGCHECK.MAX_DISPLACEMENT_dJ1 | Offset of Maximum Adjustment<br>Angle for 1 <sup>st</sup> axis (deg) | -180.0 ~ 180.0   |

|                               |                                                       |                |
|-------------------------------|-------------------------------------------------------|----------------|
| FIGCHECK.MAX_DISPLACEMENT_dJ2 | Offset of Maximum Adjustment Angle for 2nd axis (deg) | -180.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ3 | Offset of Maximum Adjustment Angle for 3rd axis (deg) | -180.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ4 | Offset of Maximum Adjustment Angle for 4th axis (deg) | -180.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ5 | Offset of Maximum Adjustment Angle for 5th axis (deg) | -180.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ6 | Offset of Maximum Adjustment Angle for 6th axis (deg) | -180.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_J7  | Offset of Maximum Adjustment Angle for 7th axis (deg) | 0.0 ~ 180.0    |
| FIGCHECK.MAX_DISPLACEMENT_J8  | Offset of Maximum Adjustment Angle for 8th axis (deg) | 0.0 ~ 180.0    |
| FIGCHECK.ERROR_DISTANCE       | Maximum Adjustment Length (mm)                        |                |

Adjustment Angle for each axis is shown in MaxDispJoint.csv file. To save the MaxDispJoint.csv file, set DEBUG.FILEOUT parameter in cOrbitGenSync.ini as 1, and the file is saved in the folder set by DEBUG.FILEPATH.

The maximum adjusted angle for each joint is defined as a sum of “the angle calculated from the maximum adjustment length” and “the offset of maximum adjustment angle (MAX\_DISPLACEMENT\_dJ\*)” for each joint.

|                |               |
|----------------|---------------|
| DEBUG.FILEOUT  | 1             |
| DEBUG.FILEPATH | Output Folder |

[Remarks] While the DEBUG.FILEOUT parameter is set to 1, the .csv file is created each time when InitNonStopPathLib or GenerateNonStopPath command is executed. Therefore, reset the DEBUG.FILEOUT parameter to 0, after the offset parameters are adjusted.

- In case of Asynchronous motion with Extended-Joint

Adjust the following parameters in cOrbitGen.ini (in Bin folder of NetwoRC Provider)

| Parameter                     | Outline                                                 | Input Limitation |
|-------------------------------|---------------------------------------------------------|------------------|
| FIGCHECK.MAX_DISPLACEMENT_dJ1 | Maximum Adjustment Angle for 1 <sup>st</sup> Axis (deg) | 0.0 ~ 180.0      |

|                               |                                                |             |
|-------------------------------|------------------------------------------------|-------------|
| FIGCHECK.MAX_DISPLACEMENT_dJ2 | Maximum Adjustment Angle for<br>2nd Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ3 | Maximum Adjustment Angle for<br>3rd Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ4 | Maximum Adjustment Angle for<br>4th Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ5 | Maximum Adjustment Angle for<br>5th Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_dJ6 | Maximum Adjustment Angle for<br>6th Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_J7  | Maximum Adjustment Angle for<br>7th Axis (deg) | 0.0 ~ 180.0 |
| FIGCHECK.MAX_DISPLACEMENT_J8  | Maximum Adjustment Angle for<br>8th Axis (deg) | 0.0 ~ 180.0 |