

# YAMAHA RCX Provider

Version 1.0.1

## User's Guide

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Remarks:

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1.0.0	2012-10-30	First edition.
	2013-04-26	Added the note for “echo-back” function of the YAMAHA controller.
1.0.1	2019-09-27	Fixed license check algorithm.

**[Hardware]**

Model	Version	Notes

**【Attention】**

**Additional license for "RCX Provider" is required to use this provider.**

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## 1. Introduction

This document is a user's guide for the CAO provider for the YAMAHA robot RCX series. The CAO provider described in this manual (CaoProvRCX.dll) is called the RCX provider.

The next chapter provides the outline of the RCX provider. Chapter 3 provides the command reference.

### 1.1. 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.

- (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.

## 2. Outline of Provider

### 2.1. Outline

The RCX provider is a CAO provider that absorbs the parts dependent on the YAMAHA robot controller and offers the functions defined in the CAO provider interface specifications. The file format is DLL (Dynamic Link Library) and the file is dynamically loaded by CAO engine when it is used. To use the RCX provider, ORiN2SDK needs to be installed or registry needs to be manually registered according to the table below.

**Table 2-1 RCX provider**

File name	CaoProvRCX.dll
ProgID	CaoProv.YAMAHA.RCX
Registry registration	regsvr32 CaoProvRCX.dll
Remove registry registration	regsvr32 /u CaoProvRCX.dll



### 2.2.1.1. Conn option

Following is communication parameter string for Conn option. Parameters inside square brackets (“[]”) can be omitted. Underlined parts represent the default values used when the option is not specified.

- **Ethernet device**

“Conn=eth:<IP Address>[:<PortNo>]”

<IP Address> : Mandatory. Destination IP address.

Example: ”127.0.0.1”, ”192.168.0.1”

<PortNo> : Destination port number.

Example: “127.0.0.1:23”, ”192.168.0.1:5010”

- **RS232C device**

“Conn=com:[<ComPort>”[:<BaudRate>[:<Parity>:<DataBits>:<StopBits>]]]”

<ComPort> : COM port number. '1'-COM1, '2'-COM2,...

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

<ByteSize> : 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

### 2.2.2. CaoController::AddRobot method

Create a CaoProvRobot object.

The robot name specified here is an arbitrary string. 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

**Table 2-3 Option character string of CaoWorkspace::AddController**

Option	Meaning
[SubRobot=<TRUE/FALSE>]	Set whether to use the RCX command for sub-robots. (Default: FALSE) This setting can be changed using the CaoRobot::ID property.



### 2.2.3. CaoController::AddVariable method

Create a variable object.

Refer to 2.3.1 about the variables implemented in the RCX provider.

**Syntax**    AddVariable(<bstrVariableName:VT\_BSTR>[,<vntOption:VT\_BSTR>])  
               < bstrVariableName >    :    [in] Variable name  
               <bstrOption>               :    [in] Option character string

#### Example

```
-----
Dim aaa As Object
Dim bbb As Double

Set aaa = caoCtrl.AddVariable("@POS")
bbb = aaa.Value
-----
```

### 2.2.4. CaoController::Execute method

Execute the command.

The arguments of the Execute method specify a command as a BSTR and a parameter as a VARIANT array.

For details about commands, refer to 3.1.

**Syntax**    [<vntRet:VT\_VARIANT>=]Execute(<bstrCmd:VT\_BSTR>[,<vntParam:VT\_VARIANT>])  
               < vntRet >                 :    [out] Return value of command  
               < bstrCmd >                :    [in] Command  
               < vntParam >               :    [in] Parameter

### 2.2.5. CaoRobot::AddVariable method

Create a variable object.

Refer to 2.3.2 about the system variables implemented in the RCX provider.

**Syntax**    AddVariable(<bstrVariableName:VT\_BSTR>[,<vntOption:VT\_BSTR>])  
               < bstrVariableName >    :    [in] Variable name  
               <bstrOption>               :    [in] Option character string

### 2.2.6. CaoRobot::Accelerate method

Set the acceleration and deceleration.

<b>Syntax</b>	Accelerate <lAxis:VT_I4>, <fAccel:VT_R4>, <fDecel:VT_R4>
< lAxis >	: [in] Axis number Set the acceleration and deceleration of the specified axis. Specify 0 for the axis number to set the acceleration and deceleration for all the axes.
< fAccel >	: [in] Acceleration Set the acceleration. Specify 0 for the acceleration to disable the acceleration setting. To set only the deceleration, therefore, specify 0 in this item.
< fDecel >	: [in] Deceleration Set the deceleration. Specify 0 for the deceleration to disable the deceleration setting. To set only the acceleration, therefore, specify 0 in this item.

### 2.2.7. CaoRobot::Change method

Change the end-effector.

<b>Syntax</b>	Change <bstrName:VT_BSTR>
< bstrName >	: [in] End-effector number

### 2.2.8. CaoRobot::Halt method

When a robot motion command of the CaoRobot class, such as the Move and Execute methods, is executed, the robot motion can be stopped using the Halt method.

<b>Syntax</b>	Halt <bstrOption:VT_BSTR>
< bstrOption >	: [in] bstrOption (not used)

### 2.2.9. CaoRobot::Move method

Move the robot to the specified position. The first argument specifies the Move command type, and the second argument specifies the destination information and speed in a VARIANT array. The following shows the argument specifications of Move.

<b>Syntax</b>	Move <lComp:VT_I4>,<vntParam : VT_VARIANT>, <bstrOpt:VT_BSTR>
<lComp >	: [in] Interpolation (VT_I4) Refer to Table 2-3. This parameter determines the execution command and the interpolation.
	1 : MOVE P
	2 : MOVE L
	3 : MOVE C
	4 : MOVEIP
<vntParam >	: [in] Destination specification Specify the destination with a character string. For details about the specification method, refer to "RCX Series Programming Manual."
<bstrOpt>	: [in] Option For the available options, refer to "RCX Series Programming Manual."

#### Example

- Example of using Move for single-axis controller

```

-----
Dim aaa As Object

Set aaa = caoCtrl.AddRobot("MF20")

caoRob.Move 1, "P13", "SPEED=50" ' 1=PTP
caoRob.Move 2, "P11"           ' 2 = Linear interpolation
caoRob.Move 3, "P10"           ' 3 = Arc interpolation
caoRob.Move 4, "P11", "S=50"   ' Move from current position to P11=170mm/deg
-----

```

**2.2.10. CaoRobot::Speed method**

Change the program speed.

**Syntax** Speed <lAxis:VT\_I4>, <fSpeed:VT\_R4>  
 <lAxis > : [in] Axis number (not used)  
 < fSpeed > : [in] Speed

**2.2.11. CaoRobot::Execute method**

Execute the command.

The arguments of the Execute method specify a command as a BSTR and a parameter as a VARIANT array.

For details about commands, refer to 3.2.

**Syntax** [<vntRet:VT\_VARIANT>=]Execute(<bstrCmd:VT\_BSTR>[,<vntParam:VT\_VARIANT>])  
 < vntRet > : [out] Return value of command  
 < bstrCmd > : [in] Command  
 < vntParam > : [in] Parameter

**2.2.12. CaoRobot::get\_ID method**

Get whether the target of the robot object is the main robot or the sub-robot.

For the description of values of IDs to be acquired, refer to Table .

**Table 2-4 ID values and robot types**

ID	Robot type
1	Main robot
2	Sub-robot

**2.2.13. CaoRobot::put\_ID method**

Switch between the main robot and the sub-robot.

For the description of values of IDs to be set, refer to Table .

**2.2.14. CaoVariable::get\_Value method**

Get the value of a variable.

For details about values to be acquired, refer to 2.3.

**2.2.15. CaoVariable::put\_Value method**

Set the value of a variable.

For details about values to be set, refer to 2.3.

## 2.3. Variable list

### 2.3.1. Controller class

**Table 2-5 Controller class system variable list**

Variable identifier	Data type	Explanation	Attribute	
			get	put
@Timeout	VT_I4	Communication timeout period The value can be specified in the Timeout option of AddController().	√	√
@CONFIG	VT_BSTR   VT_ARRAY	Get the controller configuration. The acquired information is stored in an array with the following order: <Setting name> <Axis setting> <Standard interface> <Optional device> <Other settings>	√	-
@EXELVL	VT_BSTR	Execution level status	√	-
@MOD	VT_BSTR	Mode status	√	-
@MSG	VT_BSTR	Message	√	-
@UNIT	VT_BSTR	Point unit coordinate system	√	-
@VER	VT_BSTR	Version	√	-
@MEM	VT_I4   VT_ARRAY	Available memory capacity The acquired information is stored in an array with the following order: <Source area available capacity> <Object area available capacity>	√	-
@EMG	VT_I4	Emergency stop status 0 Normal status 1 Emergency stop status	√	-
@SELFCHK	VT_BSTR   VT_ARRAY	Error status found in self check Return VT_EMPTY if there is no error.	√	-

@OPSLOT	VT_BSTR   VT_ARRAY	Return the option slot status.	√	-
---------	-----------------------	--------------------------------	---	---

**Table 2-6 Controller class user variable list**

Variable identifier	Data type	Explanation	Attribute	
			get	put
P	VT_I4   VT_ARRAY or VT_R4   VT_ARRAY	Point data Specify the point number after the variable name. The data type has six elements. A different system of unit is set depending on the data type. VT_I4   VT_ARRAY Unit: Pulse VT_R4   VT_ARRAY Unit: Millimeter	√	√
S	VT_I4   VT_ARRAY or VT_R4   VT_ARRAY	Shift data Specify the shift number after the variable name. The data type has four elements. A different system of unit is set depending on the data type. VT_I4   VT_ARRAY Unit: Pulse VT_R4   VT_ARRAY Unit: Millimeter	√	√

**2.3.2. Robot class****Table 2-7 Robot class system variable list**

Variable identifier	Data type	Explanation	Attribute	
			get	put
@ARM	VT_BSTR   VT_ARRAY	Arm status The acquired information is stored in an array with the following order: <Current arm setting status> <Arm setting status upon program reset>	√	-
@ORIGIN	VT_BSTR	Origin return status	√	-

@ABSRST	VT_BSTR	Absolute reset status	√	-
@SERVO	VT_BSTR	Servo status	√	-
@SPEED	VT_BSTR   VT_ARRAY	Speed status The acquired information is stored in an array with the following order: <Auto movement speed setting> <Manual movement speed setting>	√	-
@WHERE	VT_I4   VT_ARRAY	Current position in the pulse coordinate system of the main robot	√	-
@WHERE2	VT_I4   VT_ARRAY	Current position in the pulse coordinate system of the sub-robot	√	-
@WHRXY	VT_R4   VT_ARRAY	Current position in the millimeter coordinate system of the main robot	√	-
@WHRXY2	VT_R4   VT_ARRAY	Current position in the millimeter coordinate system of the sub-robot	√	-
@SHIFT	VT_BSTR	Shift status	√	-
@HAND	VT_BSTR	End-effector status	√	-

## 2.4. Error code

In the RCX provider, the following unique error codes are defined. For common ORiN2 errors, refer to the error code section in "[ORiN2 Programming Guide](#)".

**Table 2-8 List of original error codes**

Error name	Error code	Explanation
E_CAOP_NO_LICENSE	0x80100000	There is no license. Purchase an additional license.
RCX command error	0x8011xyyy	If an error occurs while an RCX command is executed, an error code with an error group number in xx and an error classification number in yy is returned. For description of error codes, refer to the RCX manual.

## 3. Command Reference

This chapter explains the commands of the `CaoController::Execute` and `CaoRobot::Execute` methods. For detailed operation of the commands, refer to the YAMAHA Robot Controller User's Manual.

### 3.1. Controller class

**Table 3-1 CaoController::Execute command list**

Command	Function	
EMGRST	Clear emergency stop	P.16
ArithmeticExpression	Arithmetic expression operation	P.17
StringExpression	String expression operation	P.17
PointExpression	Point expression operation	P.18
ShiftExpression	Shift expression operation	P.18
SendControlCode	Send control command	P.19
NativeSend	Send data	P.19
NativeReceive	Receive data	P.20

#### 3.1.1. CaoController::Execute("EMGRST") command

Clear the internal emergency stop flag of the RCX controller.

**Syntax** EMGRST()

Return value : None

**Example**

```
-----
caoCtrl.Execute("EMGRST") ' Clear emergency stop
-----
```



### 3.1.2. CaoController::Execute("ArithmeticExpression") command

Solve the specified arithmetic expression and get the result.

For details about specifying an arithmetic expression, refer to "RCX Series Programming Manual."

**Syntax** ArithmeticExpression( <bstrExpression:VT\_BSTR> )

< bstrExpression > : [in] Arithmetic expression (VT\_VARIANT)

Return value : [out] Operation result (VT\_R8)

#### Example

```
-----  
Dim vRes As Variant  
vRes = caoCtrl.Execute("arithmeticExpression","SQR(100 * 5)") ' 2.23606E01  
-----
```

### 3.1.3. CaoController::Execute("StringExpression") command

Solve the specified string expression and get the result.

For details about specifying a string expression, refer to "RCX Series Programming Manual."

**Syntax** StringExpression( <bstrExpression:VT\_BSTR> )

< bstrExpression > : [in] String expression (VT\_BSTR)

Return value : [out] Operation result (VT\_BSTR)

#### Example

```
-----  
Dim vRes As Variant  
vRes = caoCtrl.Execute("StringExpression", """"ABC"" + ""DEF""") 'ABCDEF  
-----
```

### 3.1.4. CaoController::Execute("PointExpression") command

Solve the specified point expression and get the result.

For details about specifying a point expression, refer to "RCX Series Programming Manual."

**Syntax** PointExpression( <bstrExpression:VT\_BSTR> )

< bstrExpression > : [in] Point expression (VT\_BSTR)

Return value : [out] Operation result

A different data type is acquired depending on the unit system of the operation result.

VT\_I4 | VT\_ARRAY Unit: Pulse

VT\_R4 | VT\_ARRAY Unit: Millimeter

#### Example

```
-----
Dim vRes As Variant
vRes = caoCtrl.Execute("PointExpression", "P1+WHRXY")
-----
```

### 3.1.5. CaoController::Execute("ShiftExpression") command

Solve the specified shift expression and get the result.

For details about specifying a shift expression, refer to "RCX Series Programming Manual."

**Syntax** ShiftExpression( <bstrExpression:VT\_BSTR> )

< bstrExpression > : [in] Shift expression (VT\_BSTR)

Return value : [out] Operation result

A different data type is acquired depending on the unit system of the operation result.

VT\_I4 | VT\_ARRAY Unit: Pulse

VT\_R4 | VT\_ARRAY Unit: Millimeter

#### Example

```
-----
Dim vRes As Variant
vRes = caoCtrl.Execute("ShiftExpression", "S1")
-----
```

### 3.1.6. CaoController::Execute("SendControlCode") command

Send a one-byte control code to the controller. For details about control codes, refer to the YAMAHA Robot Controller User's Manual.

**Syntax** SendControlCode ( <bytCode:VT\_UI1> )

< bytCode > : [in] Control code (VT\_UI1)

0x03	^C: Abort ORG, XINC, XDEC, etc.
------	---------------------------------

Return value : None

#### Example

```
-----
caoCtrl.Execute("SendControlCode", &H03)    ' Send ^C 0x03
-----
```

### 3.1.7. CaoController::Execute("NativeSend") command

Send data to the controller via Telnet communications. Specify the send command and parameters with a character string.

**Syntax** NativeSend ( <bstrNativeText:VT\_BSTR> )

< bstrNativeText > : [in] Data to send (VT\_BSTR)

Return value : None

#### Example

```
-----
caoCtrl.Execute("NativeSend", "@?ALM 0,2")    ' Send parameter "0,2" with @?ALM command
-----
```

### 3.1.8. CaoController::Execute("NativeReceive") command

Receive data from the controller via Telnet communications. Get data sent from the controller as a character string. Character strings such as "OK c/r l/f" and "NG c/r l/f" are not included.

**Syntax** NativeReceive ()

Return value : [out] Data sent from the controller (VT\_BSTR)

#### Example

```
-----
Dim aaa As String
aaa = caoCtrl.Execute("NativeReceive")           ' Receive data sent from controller
-----
```

## 3.2. Robot class

**Table 3-2 CaoRobot::Execute command list**

Command	Function	
ABSRST	Origin return of absolute motor axis	P.21
DRIVE	Absolute movement command for axis	P.21
DRIVEI	Relative movement command for axis	P.22
ORIGIN	Origin return of axis of incremental specification	P.22
PMOVE	Pallet movement command	P.23
SERVO	Servo status setting	P.23
HAND	End-effector definition	P.24
RIGHTY	Set to right-hand system	P.24
LEFTY	Set to left-hand system	P.25
SHIFT	Set shift coordinates	P.25
ARCH	Change arch position parameter	P.25
ASPEED	Auto movement speed setting	P.26
AXWGHT	Set axis tip weight	P.26
ORGORD	Set origin return processing order	P.27
OUTPOS	Set out effective position parameter	P.27
PDEF	Palette definition	P.27

TOLE	Change tolerance parameter	P.28
WEIGHT	Change tip weight parameter	P.28
TORQUE	Set torque	P.29
TRQTIME	Set torque timeout	P.29

### 3.2.1. CaoRobot::Execute("ABSRST") command

Execute origin return operation of the absolute motor axis of the robot.

**Syntax** ABSRST()

Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "ABSRST" ' Origin return
-----
```

### 3.2.2. CaoRobot::Execute("DRIVE") command

Execute absolute position movement command for an axis.

For details about specifying a position and an option character string, refer to "RCX Series Programming Manual."

**Syntax** DRIVE( < vntPoints:VT\_VARIANT | VT\_ARRAY>[, <bstrOption:VT\_BSTR>] )

< vntPoints > : [in] Movement position specification (VARIANT | VT\_ARRAY)

Movement position n	(VARIANT   VT_ARRAY)
Axis number	(VT_I4)
Position specification	(VT_BSTR)

<bstrOption> [in] Option character string (VT\_BSTR)

Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Drive", array(array(array(1, "P11"), array(2, "P10")), "S=100")
-----
```

### 3.2.3. CaoRobot::Execute("DRIVEI") command

Execute relative position movement command for an axis.

For details about specifying a position and an option character string, refer to "RCX Series Programming Manual."

**Syntax** DRIVEI(< vntPoints:VT\_VARIANT | VT\_ARRAY>[, <bstrOption:VT\_BSTR>])

< vntPoints > : [in] Movement position specification (VARIANT | VT\_ARRAY)

Movement position n	(VARIANT   VT_ARRAY)
Axis number	(VT_I4)
Position specification	(VT_BSTR)

<bstrOption> [in] Option character string (VT\_BSTR)

Return value : None

#### Example

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "DriveI", array(array(array(1, "P11"), array(2, "P10")), "S=100")
```

### 3.2.4. CaoRobot::Execute("ORIGIN") command

Execute origin return of an axis of incremental specification.

**Syntax** ORIGIN()

Return value : None

#### Example

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "ORIGIN" ' Origin return
```

### 3.2.5. CaoRobot::Execute("PMOVE") command

Execute pallet movement command.

For details about specifying an option character string, refer to "RCX Series Programming Manual."

**Syntax** PMOVE( <IPalette:VT\_I4>, <IPos:VT\_I4>[, <bstrOption:VT\_BSTR>] )

< IPalette >	:	[in] Pallet number (VT_I4)
< IPos >	:	[in] Point number (VT_I4)
< bstrOption >	:	[in] Option character string (VT_BSTR)
Return value	:	None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "PMove", Array(1, 5, "S=50")
-----
```

### 3.2.6. CaoRobot::Execute("SERVO") command

Execute pallet movement command.

If the axis number is omitted, all the axes are assumed to be specified.

**Syntax** SERVO ( <bstrState:VT\_BSTR>[, <IAxis:VT\_I4>] )

< bstrState >	:	[in] Servo status (VT_BSTR)
< IAxis >	:	[in] Axis number (VT_I4)
Return value	:	None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Servo", array("ON")
-----
```

### 3.2.7. CaoRobot::Execute("HAND") command

Define the end-effector.

**Syntax** HAND (<INo:VT\_I4>, <fPara1:VT\_R4>, <fPara2:VT\_R4>, <fPara3:VT\_R4>, <fPara4:VT\_R4>, <bROption:VT\_BOOL>)

<INo >	:	[in] End-effector number (VT_I4)
<fPara1>		[in] Parameter 1 (VT_R4)
<fPara2>		[in] Parameter 2 (VT_R4)
<fPara3>		[in] Parameter 3 (VT_R4)
<fPara4>		[in] Parameter 4 (VT_R4)
<bROption>		[in] R option (VT_BOOL)
Return value	:	None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Hand", array(1, 0, 50.0, 0, 0) ' Define HAND1 at Y axis 50mm
-----
```

### 3.2.8. CaoRobot::Execute("RIGHTY") command

Set movement in the right-hand system to the point specified in the rectangular coordinate system.

**Syntax** RIGHTY ()

Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "RIGHTY" ' Set to right-hand system
-----
```



### 3.2.9. CaoRobot::Execute("LEFTY") command

Set movement in the left-hand system to the point specified in the rectangular coordinate system.

**Syntax** LEFTY ()

Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "LEFTY" ' Set to left-hand system
-----
```

### 3.2.10. CaoRobot::Execute("SHIFT") command

Specify a shift variable and, using the shift data specified in it, set a shift coordinate.

**Syntax** SHIFT (<bstrShift:VT\_BSTR>)

<bstrShift> : [in] Shift specification (VT\_BSTR)

Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "SHIFT", "S1" ' Use S1 shift
-----
```

### 3.2.11. CaoRobot::Execute("ARCH") command

Set the arch position parameter.

If the axis number is omitted, all the axes are assumed to be specified.

**Syntax** ARCH (<IPos:VT\_I4>[, <IAxis:VT\_I4>])

<IPos> : [in] Arch position parameter (VT\_I4)

<IAxis> : [in] Axis number (VT\_I4)

Return value : None

**Example**

---

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Arch", array(100000, 2)
```

---

**3.2.12. CaoRobot::Execute("ASPEED") command**

Change the auto movement speed.

**Syntax** ASPEED (<ISpeed:VT\_I4>)

< ISpeed > : [in] Speed (VT\_I4)  
Return value : None

**Example**

---

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "ASPEED", 10
```

---

**3.2.13. CaoRobot::Execute("AXWGHT") command**

Change the axis tip weight parameter.

**Syntax** AXWGHT (<IAxis:VT\_I4>, <IVal:VT\_I4>)

< IAxis > : [in] Axis number (VT\_I4)  
< IVal > : [in] Tip weight (VT\_I4)  
Return value : None

**Example**

---

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "AxWght", array(2,5)
```

---

**3.2.14. CaoRobot::Execute("ORGORD") command**

Set the axis order parameter for origin return and absolute search operations.

**Syntax**    ORGORD (<IOrder:VT\_I4>)

< IOrder >                :    [in] Axis order parameter (VT\_I4)  
Return value                :    None

**Example**

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Orgord", 2
-----
```

**3.2.15. CaoRobot::Execute("OUTPOS") command**

Change the out effective position parameter.

If the axis number is omitted, all the axes are assumed to be specified.

**Syntax**    OUTPOS (<IPos:VT\_I4>[, <IAxis:VT\_I4>])

< IPos >                    :    [in] Out effective position (VT\_I4)  
< IAxis >                    :    [in] Axis number (VT\_I4)  
Return value                :    None

**Example**

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Outpos", array(100000, 2)
-----
```

**3.2.16. CaoRobot::Execute("PDEF") command**

Make the pallet definition used to execute the pallet movement command.

**Syntax**    PDEF (<INo:VT\_I4>, <IP12:VT\_I4>, <IP13:VT\_I4>[, <IP15:VT\_I4>])

< INo >                     :    [in] Pallet number (VT\_I4)  
< IP12 >                     :    [in] Number of points between P1-P2 (VT\_I4)

< IP13> [in] Number of points between P1-P3 (VT\_I4)  
 < IP15> [in] Number of points between P1-P5 (VT\_I4)  
 Return value : None

**Example**

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "PDef", Array(1, 3, 4, 2) ' Pallet 3x4x2
```

**3.2.17. CaoRobot::Execute("TOLE") command**

Change the tolerance parameter.

**Syntax** TOLE (<IPos:VT\_I4>[, <IAxis:VT\_I4>])

< IPos > : [in] Out effective position (VT\_I4)  
 < IAxis > [in] Axis number (VT\_I4)  
 Return value : None

**Example**

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Tole", array(1)
```

**3.2.18. CaoRobot::Execute("WEIGHT") command**

Change the tip weight parameter.

**Syntax** WEIGHT (<IVal:VT\_I4>)

< IOrder > : [in] Tip weight parameter (VT\_I4)  
 Return value : None

**Example**

```
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Weight", 20 '20kg
```

### 3.2.19. CaoRobot::Execute("TORQUE") command

Change the maximum torque command value of the specified axis.

**Syntax** TORQUE (<IAxis:VT\_I4>, <IVal:VT\_I4>)

< IAxis > : [in] Axis number (VT\_I4)  
 < IVal > : [in] Torque command value (VT\_I4)  
 Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Torque", array(2, 100) ' Maximize two axis torque
-----
```

### 3.2.20. CaoRobot::Execute("TRQTIME") command

Set the current limit timeout period for the specified axis for using the torque limit specification option of the DRIVE instruction.

**Syntax** TRQTIME (<IAxis:VT\_I4>, <IVal:VT\_I4>)

< IAxis > : [in] Axis number (VT\_I4)  
 < IVal > : [in] Timeout period (VT\_I4)  
 Return value : None

#### Example

```
-----
Dim rbt As Object
Set rbt = caoCtrl.AddRobot("MF20")
rbt.Execute "Trqtime", array(2, 2500) ' Set torque timeout to 2.5 sec
-----
```

## Appendix A. RCX Command Correspondence Table

### Appendix A.1. Controller class

- Execute method

**Table A-1 CaoController::Execute method – RCX command correspondence table**

Command name	RCX command
EMGRST	EMGRST
ArithmeticExpression	? "Arithmetic expression"
StringExpression	? "String expression"
PointExpression	? "Point expression"
ShiftExpression	? "Shift expression"
SendControlCode	-
NativeSend	-
NativeReceive	-

**Table A-2 CaoController variable object – RCX command correspondence table**

Variable identifier	RCX command
@Timeout	-
@CONFIG	?CONFIG
@EXELVL	?EXELVL
@MOD	?MOD
@MSG	?MSG
@UNIT	?UNIT
@VER	?VER
@MEM	?MEM
@EMG	?EMG
@SELFCHK	?SELFCHK
@OPSLOT	?OPSLOT
P	? "Point expression"
	Pn
S	? "Shift expression"
	Sn

## Appendix A.2. Robot class

**Table A-3 CaoRobot::Execute method – RCX command correspondence table**

Command name	RCX command
ABSRST	ABSRST
DRIVE	DRIVE
	DRIVE2
DRIVEI	DRIVEI
	DRIVEI2
ORIGIN	ORIGIN
PMOVE	PMOVE
	PMOVE2
SERVO	SERVO
	SERVO2
HAND	HAND
	HAND2
RIGHTY	RIGHTY
	RIGHTY2
LEFTY	LEFTY
	LEFTY2
SHIFT	SHIFT
	SHIFT2
ARCH	ARCH
	ARCH2
ASPEED	ASPEED
	ASPEED2
AXWGHT	AXWGHT
	AXWGHT2
ORGORD	ORGORD
	ORGORD2
OUTPOS	OUTPOS
	OUTPOS2
PDEF	PDEF
TOLE	TOLE

	TOLE2
WEIGHT	WEIGHT
	WEIGHT2
TORQUE	TORQUE
	TORQUE2
TRQTIME	TRQTIME
	TRQTIME2

**Table A-4 Methods other than CaoRobot::Execute – RCX command correspondence table**

Method	RCX command
Accelerate	ACCEL
	ACCEL2
	DECEL
	DECEL2
Change	CHANGE
	CHANGE2
Halt	^C
Move	MOVE
	MOVE2
	MOVEI
	MOVEI2
Speed	SPEED
	SPEED2

**Table A-5 CaoRobot variable object – RCX command correspondence table**

Variable identifier	RCX command
@ARM	?ARM
@ORIGIN	?ORIGIN
@ABSRST	?ABSRST
@SERVO	?SERVO
@SPEED	?SPEED
@WHERE	?WHERE
@WHERE2	?WHERE2



@WHRXY	?WHRXY
@WHRXY2	?WHRXY2
@SHIFT	?SHIFT
@HAND	?HAND