

Robot Interface CRI

V17 – December 7th, 2023

CPRog Version: V902-13-040

TinyCtrl Version: V980-13-040

Change Log

- V17 / February 13th, 2023: Added note to not implemented command ReferenceSingleExternalJoint
- V17 / January 25th, 2021: Added new parameters to PLC configuration commands and PLC triggers
- V17 / December 9th, 2021: Added status messages
- V17 / November 18th, 2021: Added cloud configuration commands
- V17 / June 11th, 2021: Added Mobile Platform commands
- V17 / February 23th, 2021: Added Get/SetActive commands for multi-client support, changed mode “joint” in STATUS message, added PROG RELATIVETOOL
- V17 / February 3rd, 2021: Added licensing commands, zero torque mode and GSIG
- V17 / January 12th, 2021: Added additional external axis config parameters, added PLC interface input inPause, PROG commands and responses implemented
- V17 / November 10th, 2020: Added virtual box error codes to KINSTATE
- V17 / July 1st, 2020: SetVariableSingle, SetVariablePosCart and SetVariablePosJoint implemented
- V17 / April 29th, 2020: GetNrVariable and GetPosVariable implemented in TinyCtrl
- V16 / January 7th, 2020: Additional RunState status message, GetReferencingInfo in CPRog, ProgramReplayMode in CPRog, GetVersion command in CPRog and TinyCtrl, GetProgramName returns Folders as well, LoadProgram open folders aswell
- V15 / April 24th, 2019: Request SystemVariables and Temperature, Changes in the Variables area. LogMessage transfer added.
- V14 / Feb. 22nd, 2019: Request/Set Variables, Start Program with Offset
- V13: UploadProgram renamed to UploadFile, changed Functionality. Referencing added. Errorcodes adapted. Referencing information added. EXECACK adapted.

1. Summary

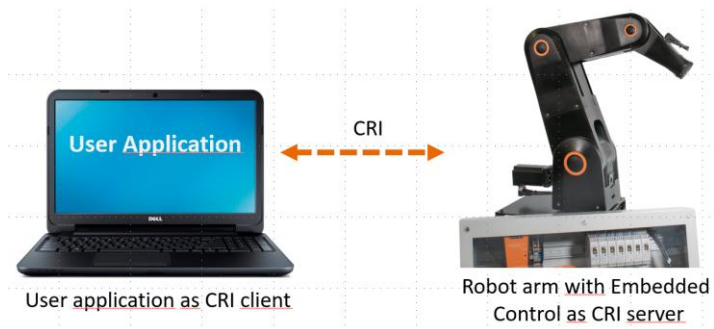
The CRI ethernet interface allows to interact with the iRC igus Robot Control and CPRog robot controls. It is available with the same interface both on the Windows software iRC or CPRog, and the Linux software of the embedded robot control.

The robot control establishes a socket server which allows a user application to connect via LAN or WLAN. The connected user application is able to remotely control the robot, including jogging, changing variable values and defining / starting robot programs.

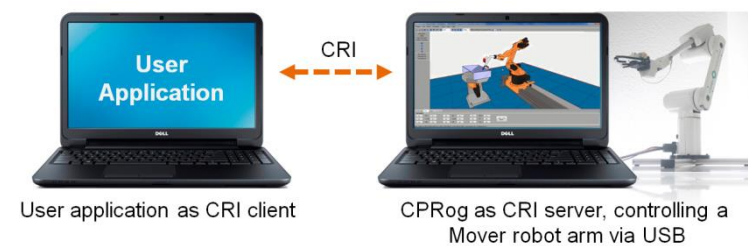
For development and testing the iRC / CPRog simulation environment can be used. For real operation only the IP address has to be changed to control the physical robot arm with an embedded control.



For the development of applications, the user application can interact with iRC igus Robot Control / CPRog. The commands are then executed by the simulated robot arm.



With the same interface a robot arm or gantry with embedded control can be addressed.



Robots without embedded control, e.g. the Mover robots, can also be commanded using the CRI interface.

In the further explanations only CPRog is mentioned as robot control software. All functionalities are the same with the iRC igus Robot Control.

2. Example Software

An example client software is available via Github:

<https://github.com/CommonplaceRobotics/CRI-DemoClient>

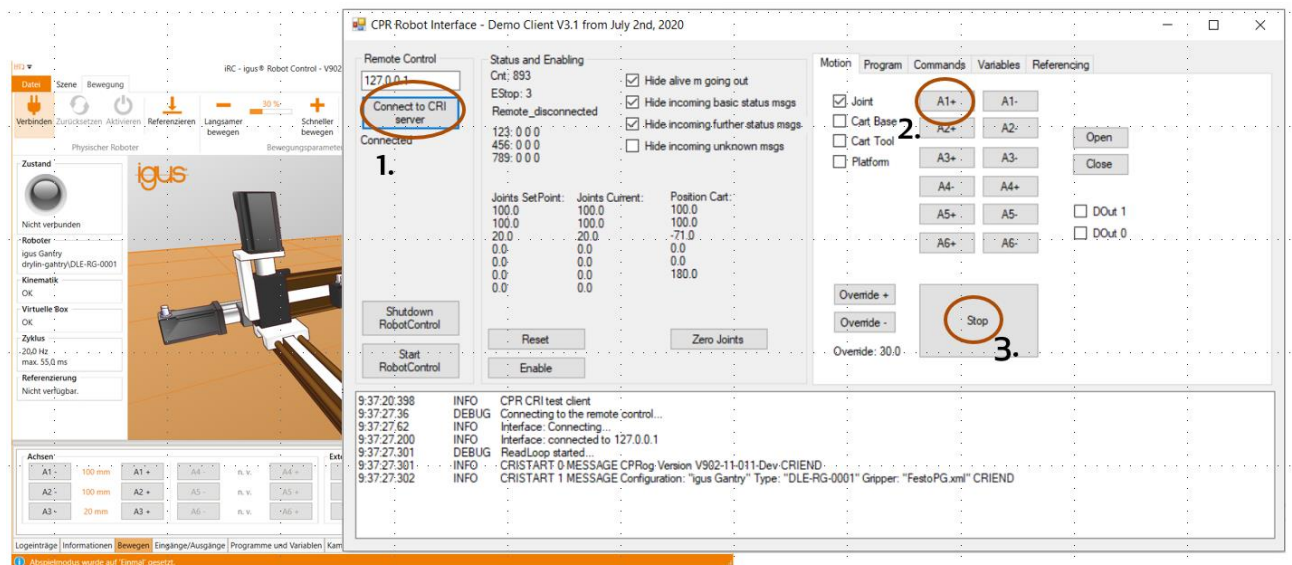
It is provided in C# source code for Microsoft Visual Studio. The software shows how to connect, how to send the control commands and how to parse the robots answers. For a stable operation of course more means regarding e.g. fault detection and error recovery have to be taken.

IP addresses are:

- Local host: 127.0.0.1
- Embedded board: 192.168.3.11, login as root without password

The client computer needs to have an IP in the same subnet, e.g. 192.168.3.1. Step by step instructions how to change the IP address can be found in the net.

A first test operation can be done with 3 steps. As preparation start CPRog and the CRI test client. The loaded CPRog project must have the CRI server activated, see chapter 3.2.



The steps are:

1. Connect the CRI test client with CPRog.
2. Choose the motion type: joint motion or linear motion in base or tool coordinate system.
3. Press e.g. the Z- button one or several times. The simulated robot will move in axis 1. Each time you press the button the velocity will increase by 10%.
4. Press the Stop button to stop all jog motions. Start the loaded robot program with the Start button.
5. For interaction with the physical robot the reset and enable buttons enable the operation.

3. Multi-Client support

Starting with CPRog/iRC V902-V12 and TinyCtrl V980-V12 multiple concurrent CRI connections are supported. Of these connections one can be active, all others are passively listening to the robot state without being able to change it.

If no active connection is present the next connection will be set active. This means that if the active client disconnects no passive client will be promoted to active state but the next new connection will be set active. Use the CMD GetActive command to check if the connection is active and the CMD SetActive command to request a passive connection to become active. Listen to the CMD Active message for state changes.

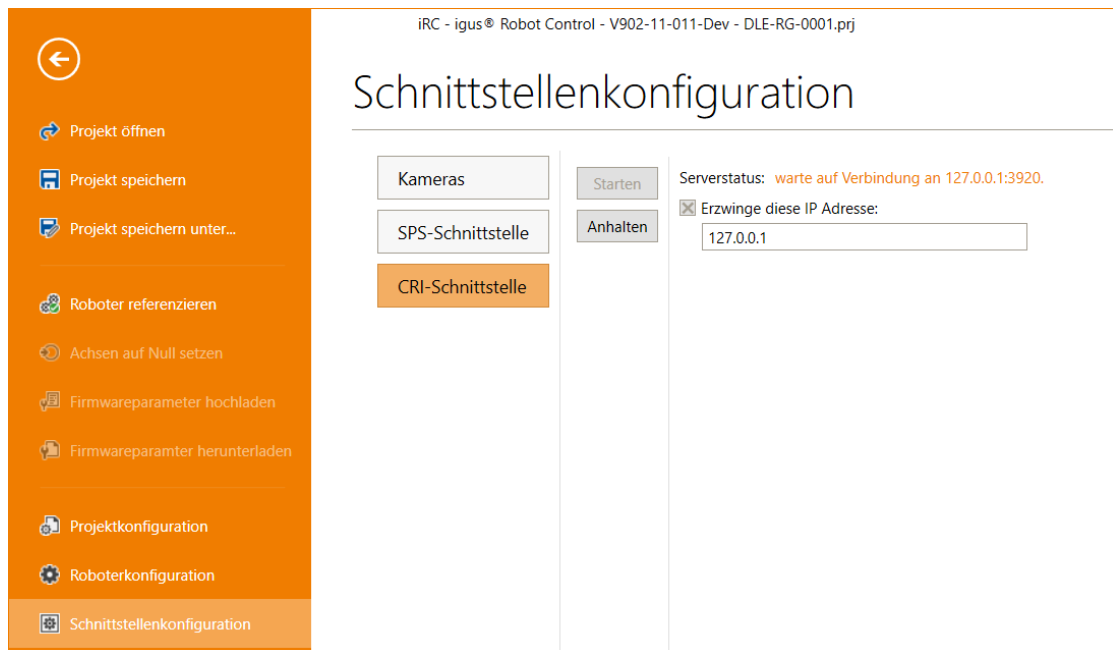
4. Definition of the CRI Interface

4.1 Interface Set Up

To allow communication the CRI server on the robot or the simulated robot needs to be activated.

On the embedded control the CRI server is active by default. In the iRC / CPRog software the CRI server needs to be activated in the backstage area as in the following picture.

- ➔ File / Interfaces / CRI Interface
- ➔ For a connection on the local computer the IP should be forced to 127.0.0.1
- ➔ Then the server can be started. The project should be saved to store these settings.
- ➔ Now the CRI demo client can connect to the CRI server.



4.2 Description

- The robot controller sets up a server. Clients can connect on Port 3920.
- When the robot controller does not receive at least one alive message every 2 seconds it will close the connection.
- 1 seconds after closing a connection the server is ready to connect to a client again.
- The operating system needs to allow the client-server connection. The according settings e.g. regarding firewalls have to be established.
- Messages to and from the server follow the scheme:
“CRISTART counter CMD_CATEGORY command_details CRIEND”
All messages from the server do have an incrementing sCnt as first parameter, the messages from the client an independent cCnt. Both are incremented with each message from 1 to 9999, then reset to 1.
- All values are sent in US style (with points as deliminators) and in mm and degree as units.

4.3 Alive Message and Status Answer

The alive message is necessary in constant time intervals, otherwise the server will declare the connection as dead and disconnect. It also defines the current jog values for the 6 arm joints and 3 gripper joints. The

jog values are float numbers in the range of [-100.0 .. 100.0]

The status answer and runstate answers from the server are generated periodically.

Both messages will not trigger an answer.

In case of an error the server will send an error message. Reason can be e.g. joint limit switches, hand singularities or similar reasons possible during jog operation:

CRISTART cCnt JOGERROR errordescription CRIEND (to be implemented)

Alive Message from Client to server (format):

CRISTART cCnt ALIVEJOG ja1 ja2 ja3 ja4 ja5 ja6 je1 je2 je3 CRIEND

No motion:

CRISTART 1234 ALIVEJOG 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 0.0 CRIEND

Jog axes (numbers are percent of max axis velocity):

CRISTART 1234 ALIVEJOG 10.0 20.0 30.0 40.0 50.0 60.0 70.0 80.0 90.0 CRIEND

Status Message from Server to Client (implemented in one line):

```
CRISTART 1234 STATUS MODE joint
POSJOINTSETPOINT 1.00 2.00 3.00 ... 15.00 16.00
POSJOINTCURRENT 1.00 2.00 3.00 ... 15.00 16.00
POSCARTROBOT 10.0 20.0 30.0 0.00 90.00 0.00
POSCARTPLATFORM 10.0 20.0 180.00
OVERRIDE 80.0
DIN 0 DOUT 0
ESTOP 3 SUPPLY 23000 CURRENTALL 2600
CURRENTJOINTS 150 200 ... 140 160
ERROR no_error 8 8 8 ... 8 8 8
KINSTATE 3
OPMODE -1
CARTSPEED 123.4
CRIEND
```

Explanations for the status answer:

- The different modes are:
 - “joint” The jog values move the robot arm (1-6) and the up to 3 additional joints in joint space. In CPRog/iRC V902-11 and older the gripper is controlled instead of additional joints.
 - “cartbase” The jog values move the robot arm in Cartesian space (base coordinate system) and the gripper in joint space.
 - “carttool” The jog values move the robot arm in Cartesian space (tool coordinate system) and the gripper in joint space.
 - “platform” A mobile platform is jogged with velocities in X, Y and RZ
 - “fsm” Jog not supported in this mode
- In POSJOINT, CURRENTJOINTS and ERROR always 16 values are provided (values are zero if the joints are not available):
 - 6 values for the robot arm joints
 - 3 values for the gripper
 - 3 values for the external joints
 - 4 values for the mobile platform joints

- Joint positions as floating point: POSJOINTSETPOINTS contains the set point joint positions in degree. POSJOINTCURRENT contains the current physical joint positions.
- Cartesian positions: values are provided in mm and degree
 - POSCARTROBOT: the XYZ and ABC values of the robot arms TCP
 - POSCARTPLATFORM: Position XY and rotation RZ of the mobile platform. These values are derived by the wheel odometry and not reliable because of drift and slipping effects.
- Override: The override value from 0 to 100 (floating point)
- DIN and DOUT: Current status of digital Inputs / Outputs, if available. Binary coding.
- ESTOP: Status of Emergency Stop (bit 1) and Main Relay (bit2). 3 means ok.
- SUPPLY: Level of the main supply in V
- CURRENTALL: Motor current for all joints measured by the safety board in mA. The current of the electronics (Linux board and joint controller) is not included.
- CURRENTJOINTS: Motor current of the single joints in mA
- ERROR: One combined error value as string and 16 single byte joint error codes.
The errors are:
 - Bit 1: Temp - Overtemperature
 - Bit 2: EStop/LowV - Supply too low
 - Bit 3: MNE Motor not enabled
 - Bit 4: COM - Communication watch dog
 - Bit 5: POS - Position lag
 - Bit 6: ENC - Encoder error
 - Bit 7: OC - Overcurrent
 - Bit 8: DRV – DriverError / SVM
- KINSTATE: Kinematic Status
 - 0: No error
 - 13,14 Joint Limit Min, Max
 - 21,23,24 Cartesian Singularities Center, Reach, Wrist
 - 30-35 Tool reached virtual box limit
 - 99 Motion not allowed, e.g. due to boards not enabled
- OPMODE: State of the safety switches (this parameter is optional and not in versions before V13)
 - -1 Operation mode not enabled
 - 0 Normal operation / auto mode: no limit
 - 1 Manual mode: Velocity limited
 - 2 No motion allowed
- CARTSPEED: Current cartesian velocity in mm/s (this parameter is optional and not in versions before V13)

Runstate Message from Server to Client (implemented in one line):

Example:

```
CRISTART 1234 RUNSTATE testmotion.xml 12 3 0 2 CRIEND
```

The robot runs the program "testmotion.xml", currently command 3 of 12 is active. The current runstate is 0 (stopped) and the replaymode is 2 (single step).

- The runstates are:
 - 0 Stopped
 - 1 Paused
 - 2 Running
- The replay modes are:
 - 0 Single
 - 1 Repeat
 - 2 Step
 - 3 Fast

Power Supply Message from Server to Client (implemented in one line):

Example:

```
CRISTART 1234 SUPPLY 78.9 CRIEND
```

If the robot is a mobile platform the battery status (charge in percent) will be regularly sent by the robot control.

4.4 Status Messages

Additional to the STATUS message the following status messages are sent automatically. They are sent at a lower frequency than the STATUS message.

```
CRISTART 1234 RUNSTATE progName commandsCnt curCommand state playmode CRIEND  
progName is the name of the currently loaded program or "None" if no program is loaded.
```

commandsCnt is the number of commands in the loaded program

curCommand is the number of the currently running (sub-)program or -1 if no program is running

state is 0 if the program is not running, 1 if it is paused, 2 if it is running

play mode is the replay mode: single run = 0, repeated = 1, step = 2

```
CRISTART 1234 GRIPPERSTATE value CRIEND
```

value is the current opening value of the gripper

```
CRISTART 1234 GSIG lower upper CRIEND
```

The values of the global signals as bitsets which are encoded as 64 bit decimal numbers. Lower describes GSig1 - GSig64, upper describes GSig65 - GSig100.

```
CRISTART 1234 OPINFO nrProgStarts upTimeComplete upTimeEnabled upTimeMotion  
upTimeLast lastProgramDuration CRIEND
```

This message includes statistics values: The total number of program starts, the total uptime, the time in enabled state, the time while moving and the uptime before the previous shutdown. lastProgramDuration is only included if supported, this value is in milliseconds.

```
CRISTART 1234 CAMINFO CameraResult type name status parameters CRIEND
```

Sends the camera results if a camera is connected and set up. Type and name as described in CONFIG SetCamera.

Status values: INACTIVE, NOTCONNECTED, CONNECTED, ERROR

Parameters depend on camera type:

Type "IFMO2D": posX posY posZ oriA oriB oriC modelClass

Type "SolutionBinPicking": posX posY posZ oriA oriB oriC modelClass

More types might be added in future.

```
CRISTART 1234 CAMINFO CameraImage name imagedata CRIEND
```

Sends the camera images if a camera is connected and set up. Name as described in CONFIG SetCamera, imagedata is either "NOIMAGE" or Base64 encoded image data.

4.5 Robot Commands

Robot commands are sent to operate the robot arm, e.g. to enable the motors, to choose the operation mode or to start and stop robot programs. The general format is:

```
CRISTART cCnt CMD commandname [parameter] CRIEND
```

The server sends an acknowledge or an error after receiving the command unless a different response is specified. The cnt number is the same as in the command message:

CRISTART sCnt CMDACK ref_to_cCnt CRIEND

CRISTART sCnt CMDERROR ref_to_cCnt error_description CRIEND

CRISTART 1234 CMD **Connect** CRIEND
 CRISTART 1234 CMD **Disconnect** CRIEND
 CRISTART 1234 CMD **Reset** CRIEND
 CRISTART 1234 CMD **Enable** CRIEND
 CRISTART 1234 CMD **Disable** CRIEND
 CRISTART 1234 CMD **SetJointsToZero** CRIEND

Only for robolink / drylin robots with reference switches:

CRISTART 1234 CMD **ReferenceAllJoints** CRIEND

Requests a referencing of all joints

CRISTART 1234 CMD **ReferenceSingleJoint** j CRIEND

Requests the referencing of a single joint.

j is the joint number starting at 0 for the first joint

CRISTART 1234 CMD **ReferenceSingleExternalJoint** j CRIEND

Not implemented! Please use ReferenceSingleJoint. Add the external axis number to the number of robot axes, e.g. "3" for the fourth axis of a 3 axis gantry, "4" for the fifth etc.

Requests the referencing of an external joint, e.g. an additional linear axis.

j is the joint number starting at 0 for the first external joint

CRISTART 1234 CMD **GetReferencingInfo** CRIEND

Sends information on the current status of the joints, if they are referenced or not. The server provides the status of the robot joints, and, if available, external joints. The information contains the general status and 12 values for the single joint referencing status.

Example answer:

CRISTART 1234 INFO ReferencingInfo 1 Joints 1 1 1 1 1 0 0 0 0 0 0 0 RefWithProg 1 1 CRIEND

Meaning: The value before "Joints" describes the robot status: 1 means that all required joints are referenced. 0 means that at least one required joint is not referenced.

The 12 values behind "Joints" are the referencing status of the single joints. In this case the first 5 joints are referenced. The external axis always start at the 7th position.

The tag "RefWithProg" and the following values are available with TinyCtrl V13-040 and newer. The first number is 1 if the referencing program is enabled to run after "reference all" and 0 otherwise. The second number is 1 if the referencing program process (including referencing) is currently running.

Available with TinyCtrl V902-13-040 and newer

CRISTART 1234 CMD **ReferenceWithProg** CRIEND

Starts the referencing program without "reference all" beforehand. The motors must be enabled and the robot must be referenced. After the program finished successfully all axes are re-referenced.

CRISTART 1234 CMD **MotionTypeJoint** CRIEND

CRISTART 1234 CMD **MotionTypeCartBase** CRIEND

CRISTART 1234 CMD **MotionTypeCartTool** CRIEND

CRISTART 1234 CMD **MotionTypePlatform** CRIEND - only with mobile base

Sets the motion type for jog motion.

Available with CPRog/iRC and TinyCtrl V902-12 and newer

CRISTART 1234 CMD **Move** <Type> 0 0 0 0 0 0 0 0 0 <velocity> CRIEND

Starts a motion to a specific position. The parameters depend on type:

Joint or RelativeJoint: 6 robot joint values, 3 external joint values.

Cart, RelativeBase, RelativeTool: 3 cartesian position values, 3 orientation values (currently not used), 3 external joint values.

In case of joint motion the last value is velocity in percent of maximum

<p>velocity (1-100). In case of cartesian the motion velocity is in mm/s. If this command is sent while an earlier motion is not finished yet the previous motion will be stopped and replaced by the new one. Robot Program execution has higher precedence than this command while this command has higher precedence than jog motion. When the target position is reached or if an error occurred the same messages will be sent as during robot program execution.</p>
<p>Available with CPRog/iRC and TinyCtrl V902-12 and newer CRISTART 1234 CMD Move Stop CRIEND Stops a CMD Move motion.</p>
<p>Available with CPRog/iRC V902-12 and TinyCtrl V980-12 or newer CRISTART 1234 CMD ZeroTorque True/False Requests to enable/disable the zero-torque mode. This has no effect if this mode is not enabled in the robot configuration file. Motor modules must support torque mode. After disabling the motors are in Disabled state. CRISTART 1234 CMD ZeroTorque Requests information on the zero-torque mode. Both commands send the following reply: CRISTART 1234 CMD ZeroTorque <allowed> <enabled> Both parameters are True/False. <allowed> shows whether zero torque mode is enabled in the robot configuration, <enabled> shows whether it is enabled.</p>
<p>CRISTART 1234 CMD DOUT 3 true CRIEND Sets the state of a digital output. The DOut number is 0 .. 63. This has no effect if a program is running.</p>
<p>Available with CPRog/iRC V902-12 and TinyCtrl V980-12 or newer CRISTART 1234 CMD GSIG 3 true CRIEND Sets the state of a global signal. The GSig number is 0 .. 99. A status message in the following format is sent periodically: CRISTART 1234 GSIG lower upper CRIEND lower and upper are 64 bit decimal numbers encoding the global signal states.</p>
<p>CRISTART 1234 CMD Override ovr CRIEND Sets the override for jog motion and replay. ovr is a floating-point value from 0.0 to 100.0</p>
<p>CRISTART 1234 CMD GetVersion CRIEND Requests the Software name ("TinyCtrl" or "CPRog") from the server along with the protocol version implemented by the server. Example answer: CRISTART 1234 INFO Version CPRog 16 CRIEND In this case the server is CPRog and implements CRI-Commands up to protocol version 16.</p>
<p>CRISTART 1234 CMD StartProgram CRIEND CRISTART 1234 CMD StopProgram CRIEND CRISTART 1234 CMD PauseProgram CRIEND CRISTART 1234 CMD ProgramReplayMode replayMode CRIEND <i>replayMode</i> is an integer defining the replay mode for the current and further programs started. <i>replayMode</i> = 0 Single replay <i>replayMode</i> = 1 Repeated replay <i>replayMode</i> = 2 Stepwise replay, the replay is paused after each command and has to be continued with the <i>StartProgram</i> command.</p>
<p>Available on TinyCtrl only. CRISTART 1234 CMD StartProgramWithOffset j0 .. j8 x y z a b c CRIEND Starts a program with the defined offset values. The offset values are added to the target positions of Joint/JointbyVariable and Linear/LinearbyVariable motions. They do not affect relative motions.</p>

The offsets are valid until another program is loaded, the automatic restart or the manual start do not change the offsets. The use of the StartProgram command as above (e.g. when pressing on Start in CPRog) or loading a program will reset the offset to zero.

Setting and resetting the offsets will generate a logfile entry.

Attention: There is no check for validity of the values, if the values are e.g. too high the program will stop with an out-of-reach error or similar.

j0 .. j8 are the 9 floating point offsets for the 9 possible joints

x .. c are the floating point offsets for the cartesian coordinates

Example:

```
CRISTART 6789 StartProgramWithOffset 10 -10.0 5 -5.0 0.0 0.0 0.0 0.0 0.0 0.0 30.0
20.0 10.0 0.0 0.0 0.0 CRIEND
```

CRISTART 1234 CMD StartAt progName commandIndex CRIEND

Sets the command to start at. This command has no effect if a program is running.

If the program file progName is not loaded yet it will be loaded. The program is set to paused and the command commandIndex (starting at 0 for the first command) is set to be the next command.

After the requested program finishes: The parent program will continue if the requested program was paused at. Otherwise execution will stop.

CRISTART 1234 CMD LoadProgram progName CRIEND

Load a program file from disk into the robot controller. progName is the name in the Directory /Data/Programs/, e.g. "test.xml". Programs loaded before are erased. The program is loaded as program 0. From CRI version 16 onwards, this command can also be used to open a folder.

CRISTART 1234 CMD LoadLogicProgram progName CRIEND

Available in CRI version 16 and newer

Load a logic program file from disk into the robot controller. progName is the name in the Directory /Data/Programs/, e.g. "test.xml". Programs loaded before are erased. The program is loaded as program 0.

CRISTART 1234 CMD DeleteProgram CRIEND

Removes all loaded programs from the robot control (not from the disk). This commands should be called before assembling a new program with Add-commands.

CRISTART 1234 CMD DeleteLogicProgram CRIEND

Removes all logic programs from the robot control (not from the disk).

CRISTART 1234 CMD DeleteProgramFromFileSystem progName CRIEND

Available on TinyCtrl only.

Deletes the file progName in the /Data/Programs/ directory permanently. It is removed from the disk and cannot be restored.

"progName" has to be the filename of the program, e.g. "testmotion.xml". The path /Data/Programs/ is added automatically.

CRISTART 1234 CMD GetProgramInfo CRIEND

Sends an answer with the currently active programs name, the number of commands in the program and the currently active command.

Example:

```
CRISTART 1234 INFO ProgramInfo testmotion.xml 12 3 CRIEND
```

The robot runs the program "testmotion.xml", currently command 3 of 12 is active.

CRISTART 1234 CMD GetLogicProgramInfo CRIEND

Available in CRI version 16 and newer

Sends an answer with the currently active logic programs name, the number of commands in the program and the currently active command.

```
CRISTART 1234 INFO LogicProgramInfo testmotion.xml 12 3 CRIEND
```

CRISTART 1234 CMD GetProgramName which CRIEND

Available on TinyCtrl only.

Sends an answer with the number of files in directory /Data/Programs/, and the filename of one of the files. From CRI version 16 onwards this command also enumerates folders (distinguished by a trailing slash character).

Example:

```
CRISTART 1234 INFO ProgramName testmotion.xml 0 7 CRIEND
```

The first of seven programs has the name "testmotion.xml"

-- Changed Command Name and behavior due to broader focus --

CRISTART 1234 CMD UploadFileInit fileName nrOfLines CRIEND

To upload a file to the /Data/ directory a combination of the commands *UploadFileInit*, *UploadFileLine* and *UploadFileFinish* has to be send. These commands only write the file to the drive. The file has to be loaded afterwards using *LoadProgram*.

UploadFileInit initializes the upload. *fileName* is a string with the file name relative to the /Data/ directory (this means that you need to prepend "Programs/" to your program name).

nrOfLines is an integer with the number of *UploadFileLine* commands following. Between sending the lines there should be small breaks to allow sending the Alive messages.

-- Changed Command Name due to broader focus --

CRISTART 1234 CMD UploadFileLine fileLine CRIEND

For every line of the original file one command *UploadFileLine* has to be send. *fileLine* is a string with the line to be written.

-- Changed Command Name due to broader focus --

CRISTART 1234 CMD UploadFileFinish CRIEND

This command finishes the file upload by closing it. It also compares the received number of lines with the anticipated number.

Supported in CPProg/iRC/TinyCtrl V12 and newer

CRISTART 1234 CMD GetActive CRIEND

CRISTART 1234 CMD SetActive true/false CRIEND

GetActive requests the active/passive state of the CRI connection. If the connection is passive all commands that change the state of the robot control will be ignored. *SetActive* requests the CRI connection to set active or passive, in the former case all connections to other clients will be set passive.

The following response will be sent by both requests and on state change:

```
CRISTART 1234 CMD Active true/false CRIEND
```

4.6 System Commands

CRISTART 1234 SYSTEM Shutdown <number> CRIEND

<number> = 99: Stops the robot control software (only implemented in TinyCtrl)

<number> = 100: Shuts down the entire system (implemented in V12 and newer)

<number> = 101: Sends a restart message to the motor modules (implemented in V13 and newer, not supported by all module versions)

CRISTART 1234 SYSTEM GetBoardTemp CRIEND

Provides the temperatures of the motor control PCBs.

Example Request:

```
CRISTART 1234 SYSTEM GetBoardTemp CRIEND
```

Example Answer:

```
CRISTART 6789 INFO BoardTemp temp1 temp2 ... temp16 CRIEND
```

temp1 to temp16 are the PCB temperatures of the joint 1 to 16. The values are °C transmitted as floating point numbers.

```
CRISTART 1234 SYSTEM GetMotorTemp CRIEND
```

Not implemented yet.

4.7 Log Messages

The remote systems can transfer its log messages to the CRI client. This functionality can be switched on or off in the ini files of the remote system.

Implemented in TinyCtrl, currently not in CPRog

```
CRISTART 1234 LOGMSG msgString CRIEND
```

Provides the log messages from the remote system. They can be used e.g. for diagnostics.

4.8 Handling of Variables

CRISTART 1234 VAR GetNrVariable variableName CRIEND

Sends an answer with the value of a number variable. The result is one float value. The variable must be defined in the running robot or logic program and the program must have passed the defining Store command.

Example of an answer:

```
CRISTART 1234 VARINFO ValueNrVariable currentRow 3.0 CRIEND
```

The variable currentRow has the value 3.0.

Example of an answer in case of an error, e.g. when the variable is not known:

```
CRISTART 6789 VARERROR ValueNrVariable currentRow variable_not_known CRIEND
```

CRISTART 1234 VAR GetPosVariable variableName CRIEND

Sends an answer with the value of a position variable. The result is 15 float values. The variable must be defined in the running robot or logic program and the program must have passed the defining Store command.

Example of an answer (x-z, A-C, a1-a6 and e1-e3 will be float values):

```
CRISTART 1234 VARINFO ValuePosVariable currentPos x y z A B C a1 a2 a3 a4 a5 a6 e1 e2 e3 CRIEND
```

Example of an answer in case of an error, e.g. when the variable is not known:

```
CRISTART 6789 VARERROR ValuePosVariable currentPos variable_not_known CRIEND
```

CRISTART 1234 VAR GetSystemVariable variableNumber CRIEND

Sends an answer with the value of a system variable. The result is one int value.

System variables are (number, name and meaning):

0	UpTimeComplete	Time the control is running [Minutes]
1	UpTimeLast	Time the control is running since the last start [Minutes]
2	UpTimeEnabled	Time the control was in "NoError" state [Minutes]
3	UpTimeMotion	Time the robot has been moving [Minutes]
4	ProgramStarts	Number of starts of the main program
10	JointCycles	Number of direction changes in joint 1
..		
18	JointCycles	Number of direction changes in joint 9

Example of an answer:

```
CRISTART 1234 VARINFO ValueSystemVariable 0 Value 10429 CRIEND
```

The control has been running for 10429 minutes.

Example of an answer in case of an error, e.g. when the variable is not known:

```
CRISTART 6789 VARERROR ValueSystemVariable 22 variable_not_known CRIEND
```

The system variable number 22 is not known.

Implemented in CPRog V902-11-011 and TinyCtrl V980-11-088 and newer

CRISTART 1234 VAR SetVariableSingle variableName newValue CRIEND

Sets the value of a variable. The argument variableName can be the name of a number variable (e.g. nrOfRows). It cannot be an element of a position variable (e.g. targetPos.x).

The variable must be defined in the running robot or logic program and the program must have passed the defining Store command.

Standard answer is an acknowledgement:

```
CRISTART 6789 CMDACK 1234 CRIEND
```

Example of an answer in case of an error, e.g. when the variable is not known:

```
CRISTART 6789 CMDERROR 1234 variable_not_known CRIEND
```

Implemented in CPRog V902-11-011 and TinyCtrl V980-11-088 and newer

CRISTART 1234 VAR SetVariablePosCart variableName x y z a b c e1 e2 e3 CRIEND

Sets the value of a variable. The argument variableName is the name of a

position variable (e.g. targetPos). The Cartesian elements of the variable are updated. The joint elements of the variable remain on their old values. The variable must be defined in the running robot or logic program and the program must have passed the defining Store command.

Standard answer is an acknowledgement:

CRISTART 6789 CMDACK 1234 CRIEND

Example of an answer in case of an error, e.g. when the variable is not known:

CRISTART 6789 CMDERROR 1234 variable_not_known CRIEND

Implemented in CPRog V902-11-011 and TinyCtrl V980-11-088 and newer

CRISTART 1234 VAR SetVariablePosJoint variableName j0 j1 .. j5 e1 e2 e3 CRIEND

Sets the value of a variable. The argument variableName is the name of a position variable (e.g. targetPos). The joint elements of the variable are updated. The cartesian elements of the variable remain on their old values. The variable must be defined in the running robot or logic program and the program must have passed the defining Store command.

Standard answer is an acknowledgement:

CRISTART 6789 CMDACK 1234 CRIEND

Example of an answer in case of an error, e.g. when the variable is not known:

CRISTART 6789 CMDERROR 1234 variable_not_known CRIEND

4.9 Defining a Robot Program

The following messages add robot commands to the currently loaded program on the robot control. To take effect the robot program must be started using the CMD messages (start, pause, stop). The deletion of all commands can also be done using the CMD message.

With the cmdCnt number the client can provide an id to the program command. This id is used when there are further messages regarding the program command, e.g. error or execution acknowledgments.

The server sends an acknowledgement or an error after receiving the message, the cnt number is the same as in the command message.

```
CRISTART sCnt PROGACK ref_to_cCnt ref_to_cmdCnt CRIEND
```

```
CRISTART sCnt PROGERROR ref_to_cCnt ref_to_cmdCnt errordescription CRIEND
```

Currently the following error descriptions are used: unknown_command, incomplete_argument, could_not_parse, system_error

CRISTART cCnt PROG cmdCnt JOINT j0 ... j5 EXT j6...j8 VEL velpercent CRIEND

Example: CRISTART 1234 PROG 42 JOINT 10.00 20.00 30.00 40.00 50.00 60.00 EXT 70.0 80.0 90.0 VEL 20.0 CRIEND

Adds a joint command to the current robot program. The joint values (degree, floating point) for the 6 robot joints and 3 additional joints are defined. The VEL parameter (percent [0..100] floating point) defines the joint velocity in percent.

During replay all joints move with a constant velocity to the set point values, the velocities depend on the joint with the longest travel time.

Implemented in CPRog V902-11-024 and TinyCtrl V980-11-102 and newer

CRISTART cCnt PROG cmdCnt RELATIVEJOINT j0 ... j5 EXT j6...j8 VEL velpercent CRIEND

Example: CRISTART 1234 PROG 42 RELATIVEJOINT 10.00 20.00 30.00 40.00 50.00 60.00 EXT 70.0 80.0 90.0 VEL 20.0 CRIEND

Adds a relative joint command. The parameters are as described for the JOINT command.

CRISTART 1234 PROG cmdCnt LINEAR x y z a b c EXT j6...j8 VELMMS velmms CRIEND

Example: CRISTART 1234 PROG cmdCnt LINEAR 10.0 20.0 30.0 40.0 50.0 60.0 EXT 70.0 80.0 90.0 VELMMS 20.0 CRIEND

Adds a linear command to the current robot program. The x-z, a-c values define a cartesian base coordinate, j6-j8 define additional joints. The VEL parameter defines the linear velocity in mm/s.

Implemented in CPRog V902-11-024 and TinyCtrl V980-11-102 and newer

CRISTART 1234 PROG cmdCnt RELATIVELINEAR 50.0 50.0 50.0 125.0 CRIEND

Adds a linear command that does a movement relative to the base coordinate system. The values are x, y and z cartesian coordinates, the fourth value is the motion speed in mm/s. All values are float.

Implemented in CPRog V902-11-025 and TinyCtrl V980-11-104 and newer

CRISTART 1234 PROG cmdCnt RELATIVETOOL 50.0 50.0 50.0 125.0 CRIEND

Adds a linear command that does a movement relative to the tool coordinate system. The values are x, y and z cartesian coordinates, the fourth value is the motion speed in mm/s. All values are float.

CRISTART 1234 PROG cmdCnt GRIPPER grpJoint1 jrpJoint2 grpJoint3 CRIEND

Example to open the gripper: CRISTART 345 PROG 81 GRIPPER 100.0 0.0 0.0 CRIEND

Adds a Gripper statement to the end of the current robot program.

cmdCnt is an integer as reference to the command

grpJoint1 to 3 are floating point values for the gripper joints ranging from 0.0 to 100.0. A maximum of 3 gripper joints can be commanded (currently only one is supported!). For single joint gripper only the first value is used.

The robot control does not wait for the execution of this command, the next command is issued in the next cycle. It might be necessary to add a wait command after the gripper command e.g. to ensure that the workpiece gets gripped.

CRISTART 1234 PROG cmdCnt WAIT timeInMS CRIEND

Example to wait 5 seconds: CRISTART 827 PROG 23 WAIT 5000 CRIEND

Adds a wait statement to the end of the current robot program.

cmdCnt is an integer as reference to the command

timeInMS is the wait time in milliseconds

Implemented in CPRog V902-11-024 and TinyCtrl V980-11-102 and newer

CRISTART 1234 PROG cmdCnt DOUT doutNum true CRIEND

Adds a command that enables or disables a digital output. The *doutNum* is offset by 1 in the CPRog UI, this means that DOut21 in CPRog is number 20 in this command.

4.10 Execution of Robot Programs

Available in CPRog: n/a

Available in TinyCtrl: from Version V980-04-041

After the start of a robot program the server sends messages regarding the current execution status to the client, e.g. "just started execution of command nr 462" or "just reached end of linear motion nr 90".

```
CRISTART sCnt EXECACK cmdNr progNr CRIEND
```

When the program is paused the following message is generated:

```
CRISTART sCnt EXECPAUSE cmdNr progNr CRIEND
```

When the program execution ends an according message is generated:

```
CRISTART sCnt EXECEND cmdNr progNr reason CRIEND
```

In the case of an error during execution an according message is generated:

```
CRISTART sCnt EXECERROR cmdNr progNr errordescription CRIEND
```

Parameter	Type	Description
cmdNr	Int	The command currently being executed in the program progNr
progNr	Int	The nr of the program currently being executed. The nr refers to the programs loaded in the robot controller, not to the files in the folder /Data/Programs. For single programs this parameter is 0. When there are subprograms this parameter can be 1, 2, ..., depending on the nr of subprograms.
reason	String	Reason for stopping the execution: PLAN Program finished correctly as programmed USER The user stopped the program execution PLC The PLC interface stopped the program exec. ERROR An external error stopped the execution, e.g. emergency stop.
errordescription	String	Description of the error, e.g. "JointLimits Min exceeded..." Only program execution errors are listed here, not external errors that cause a fault in the complete robot system (emergency stop, overtemperature, ...) These are available interpreting the error code and the EXECEND reason.

Remarks:

- When the robot executes the program in "repeat" mode the EXECEND message is not sent.
- When pausing and restarting a program there will be two EXECACK messages for the current command: one when the command is getting active in the program flow before pausing; the second when the command is reactivated after resuming.

- The EXECERROR messages is send e.g. when joint min/max values are exceeded, or in case of singularities.
- If the robot does not start a program, e.g. due to an error or due to missing referencing, there will be no EXECACK message.

4.11 Configuration Commands

Available in CPRog: from version V902-11

Available in TinyCtrl: from version V980-11

The configuration commands are sent to the robot to query or change configuration parameters.

CRISTART 1234 CONFIG SetDIOModules canID1 canID2 canID3 CRIEND Enables or disables DIO modules and sets their CAN IDs. The parameters canID1 to canID3 can be 0 to disable a module or a CAN ID value up to 255. If one of the canIDs is 0 all following IDs must be 0. TinyCtrl will write this change to its project configuration file.
CRISTART 1234 CONFIG GetDIOModules CRIEND Requests the CAN IDs of the DIO modules. The response contains the CAN IDs as described in SetDIOModules: CRISTART 1234 CONFIG DIOModules canID1 canID2 canID3 CRIEND
CRISTART 1234 CONFIG SetDOutDefaults ResetStates0-31 ResetStates32-63 ErrorStates0-31 ErrorStates32-63 CRIEND Sets the DOut states that are set on reset and error. The parameters are 64 bit unsigned integers. Each two bit represent one DOut port: 00 false 01 true 10 no change 11 reserved
CRISTART 1234 CONFIG GetDOutDefaults CRIEND Requests the DOut default values as described in SetDOutDefaults. CRISTART 1234 CONFIG DOutDefaults ResetStates0-31 ResetStates32-63 ErrorStates0-31 ErrorStates32-63 CRIEND
Implemented in CPRog only, available for gantry robots only CRISTART 1234 CONFIG SetGantryLength x y z CRIEND Sets the axis length of a portal robot for visualization purposes. Use SetKinematicLimits to change the kinematic axis lengths. The parameters are floating point values. TinyCtrl will write this change to its robot configuration file.
Implemented in CPRog only, available for gantry robots only CRISTART 1234 CONFIG GetGantryLength CRIEND Requests the axis length of a gantry robot as described in SetGantryLength. Response: CRISTART 1234 CONFIG GantryLength x y z CRIEND
Implemented for gantry robots only CRISTART 1234 CONFIG SetKinematicLimits minValue maxValue CRIEND Sets the kinematic axis lengths. The number of parameters depends on the robot type, the upper limit is 9 pairs of minimum and maximum values. The parameters are floating point values. TinyCtrl will write this change to its robot configuration file.
Implemented for gantry robots only CRISTART 1234 CONFIG GetKinematicLimits CRIEND Requests the kinematic axis lengths. The response contains up to 9 value pairs as described in SetKinematicLimits: CRISTART 1234 CONFIG KinematicLimits minValue maxValue CRIEND
CRISTART 1234 CONFIG SetPLCInterface inEnable inRequestReference inPlay outNoFault outProgramRunning outRobotIsReferenced inPause inAltStart inAltStop inShutdown inAddJointCommand inAddLinearCommand outError outProgramNotRunning outPlatformMissionRunning CRIEND Sets the PLC interface numbers. The parameters are integer numbers, -1 means the input or output is disabled. All parameters after outRobotIsReferenced are optional. Parameters after inPause are supported with Version CPRog/iRC and TinyCtrl 13-014 and newer.

TinyCtrl will write this change to its project configuration file.
CRISTART 1234 CONFIG GetPLCInterface CRIEND Requests the PLC interface numbers. The response contains these values as described in SetPLCInterface. Parameters after outRobotIsReferenced will only be sent if they are supported. CRISTART 1234 CONFIG PLCInterface inEnable inRequestReference inPlay outNoFault outProgramRunning outRobotIsReferenced inPause inAltStart inAltStop inShutdown inAddJointCommand inAddLinearCommand outError outProgramNotRunning outPlatformMissionRunning CRIEND
CRISTART 1234 CONFIG SetPLCInterfaceEnabled active autoConnect CRIEND Enables or disables the PLC interface and the auto connect function. active and autoConnect must be 'True' or 'False'. TinyCtrl will write this change to its project configuration file.
CRISTART 1234 CONFIG GetPLCInterfaceEnabled CRIEND Requests the PLC enabled and autoConnect states. The response contains these values as described in SetPLCInterfaceEnabled: CRISTART 1234 CONFIG PLCInterfaceEnabled active autoConnect CRIEND
CRISTART 1234 CONFIG GetPLCTriggers CRIEND Requests the PLC program trigger configuration. The response are one or more messages of the following format: CRISTART 1234 CONFIG PLCTrigger 0 0 No PLC triggers configured CRISTART 1234 CONFIG PLCTrigger num cnt active signalType signalNum targetType filename PLC program trigger definition. Num is the index of the specified trigger (starting at 0), cnt is the count of all triggers. Active can be "True" or "False", signalType can be "DIn" or "GSig", signalNum is the number of the input, it may be negative if invalid. targetType is the type of program that is triggered: "Program" or "Mission". Filename is the path of the program, relative to Data/Programs/ or Data/Missions/. It may be "none" if no program is defined. More parameters may be added in future. Space characters are not allowed.
CRISTART 1234 CONFIG ClearPLCTriggers CRIEND Removes all PLC triggers.
CRISTART 1234 CONFIG AddPLCTrigger active signalType signalNum targetType filename CRIEND Adds a PLC program trigger. The parameters are defined as described in GetPLCTriggers.
CRISTART 1234 CONFIG SetBrake brakeDOut delay estopDIn CRIEND Sets the brake DOut number and the E-Stop monitoring Din number. Max 63, -1 to disable. Delay is the brake release delay in ms. Older robot controls only support brakeDOut.
CRISTART 1234 CONFIG GetBrake CRIEND Requests the brake DOut number and the E-Stop monitoring Din number. If disabled -1 is returned. Delay is the brake release delay in ms. Older robot controls may only send brakeDOut. CRISTART 1234 CONFIG Brake brakeDOut delay estopDIn CRIEND
CRISTART 1234 CONFIG SetProgramDefaultState defaultState CRIEND defaultState is an integer defining the default state after an error or reset. defaultState = 0 Paused defaultState = 1 Stopped
CRISTART 1234 CONFIG GetProgramDefaultState CRIEND Requests the program default state as defined in SetProgramDefaultState. CRISTART 1234 CONFIG ProgramDefaultState defaultState CRIEND
CRISTART 1234 CONFIG SetCamera type name parameters CRIEND Sets camera parameters. The parameters depend on the type: Type "None": No parameters, removes the camera if it exists. Type "IFM02D" (IFM O2D camera): active IP port scaleX scaleY originX originY originZ lookX lookY lookZ upY upY upZ zDistance imageEnabled [coordinate type] Type "SolutionBinPicking": active IP port originX originY originZ lookX lookY

<p>lookZ upY upY upZ zDistance imageEnabled active and imageEnabled must be 'True' or 'False', IP must be IPv4 address string, port must be integer, all further parameters are floating point numbers. Coordinate type is 0 for image coordinates (px) or 1 for robot coordinates (mm). More types might be added in future.</p>
<p>CRISTART 1234 CONFIG GetCameras CRIEND Requests all camera configurations. Each camera configuration will be sent as a separate response in the following format: CRISTART 1234 Camera count type name parameters CRIEND Count is the total number of cameras. Type, name and parameters are as described in SetCamera.</p>
<p>CRISTART 1234 CONFIG ClearCameras CRIEND Removes all cameras.</p>
<p>Deprecated since V13 CRISTART 1234 CONFIG SetExternalAxes number [parameters] [parameters] [parameters] CRIEND Sets the external axes configuration. Number describes the number of external axes, 0 disables all external axes (only 0-1 supported in CPRog/iRC <= V902-11-023 and TinyCtrl <= V980-11-100). For each external axis a set of parameters follows in the following format: Type kinematic canid gearscale min max velmax acc accinc [directionAngleToY lz0 dir offset] Type is a string stating the axis type. It must not contain a whitespace. "na" if no type is given. Kinematic must be "Dependent" or "Independent" Canid is the CAN-module ID The last four parameters may be missing if only one axis is specified and are only relevant if kinematic is set to "Dependent". This configuration will only be applied after saving the project and reloading it (CPRog/iRC) or restarting the robot control (TinyCtrl)</p>
<p>CRISTART 1234 CONFIG SetExternalAxis axisCnt number kinematic jointMode canid gearscale min max velmax acc accinc directionAngleToY lz0 dir offset CRIEND Sets the configuration of an external axis. axisCnt is the total number of external axes or 0. Existing axes exceeding this number will be removed. Number is the number of this axis (0-2). jointMode is either "position", "velocity" or "torque". The other parameters are as described in SetExternalAxes. More parameters may be added in future. This configuration will only be applied after saving the project and reloading it (CPRog/iRC) or restarting the robot control (TinyCtrl)</p>
<p>Deprecated since V13 CRISTART 1234 CONFIG GetExternalAxes CRIEND Requests the external axes configuration. The parameters are as described in SetExternalAxes. CRISTART 1234 CONFIG ExternalAxes number [parameters] [parameters] [parameters] CRIEND</p>
<p>CRISTART 1234 CONFIG GetExternalAxes2 CRIEND Requests the external axes configuration. Each axis will be sent as a separate message. The parameters are as described in SetExternalAxis. cntTotal is the total number of external axes, number is the index of the axis specified in this message. CRISTART 1234 CONFIG ExternalAxis cntTotal number kinematic jointMode canid gearscale min max velmax acc accinc directionAngleToY lz0 dir offset CRIEND If no external axis is configured the following message will be sent: CRISTART 1234 CONFIG ExternalAxis 0 0 CRIEND</p>
<p>Implemented in TinyCtrl V12-020 and newer. CRISTART 1234 CONFIG SetModbus active port maxConnections CRIEND Configures the Modbus server. Active must be 'True' or 'False', port must be a</p>

number of the range 0 - 65535 (standard is 502), maxConnections must be a number greater than 0, standard is 5.
Implemented in TinyCtrl V12-020 and newer. CRISTART 1234 CONFIG GetModbus CRIEND Requests the Modbus server configuration. Parameters are as described in SerModbus. Response: CRISTART 1234 CONFIG Modbus active port maxConnections CRIEND
CRISTART 1234 CONFIG SetTool filename [parameters for future use] CRIEND Sets the tool configuration filename or "none" to remove the tool. The file must be present at the robot control. Optional parameters might be added in future. TinyCtrl must be restarted for this command to take effect. The following response will be sent if the file does not exist: CRISTART 1234 CONFIGERROR Tool invalid file CRIEND
CRISTART 1234 CONFIG GetTool CRIEND Requests the tool configuration filename. Optional parameters might be added in future. CRISTART 1234 CONFIG Tool filename [parameters for future use] CRIEND
CRISTART 1234 CONFIG SetVBox enabled xmin xmax ymin ymax zmin zmax CRIEND Sets the virtual box configuration. 'enabled' must be True or False, the parameters are float values.
CRISTART 1234 CONFIG GetVBox CRIEND Requests the virtual box configuration as described for SetVBox. CRISTART 1234 CONFIG VBox enabled xmin xmax ymin ymax zmin zmax CRIEND
Implemented in CPRog V902-13-022 and TinyCtrl V980-13-022 and newer CRISTART 1234 CONFIG SetCloudConnection enabled CRIEND CRISTART 1234 CONFIG SetCloudConnection enabled "MyClientID" "CloudUser" "Passwd" CRIEND Sets the cloud connection information: 'enabled' enables the cloud interface, it must be True or False. The client ID must be unique for the given cloud user. CloudUser is the registration email-address on RobotDimension, Passwd is the robot password that can be set on RobotDimension. The password may contain special characters including whitespace. If client ID, user or password is empty ("") the cloud interface will be disabled. Quotation marks must be used.
Implemented in CPRog V902-13-022 and TinyCtrl V980-13-022 and newer CRISTART 1234 CONFIG SetCloudInfo "robot name" "robot owner" CRIEND Sets the optional information that will be sent to the cloud. The parameters may include special characters including whitespace. Quotation marks must be used. Further parameters may be added in future.
Implemented in CPRog V902-13-022 and TinyCtrl V980-13-022 and newer CRISTART 1234 CONFIG GetCloud CRIEND Requests the cloud information. The following response will be sent. This message will also be sent automatically if the connection state changes. Further parameters may be added to the response in future. CRISTART 1234 CONFIG Cloud enabled areCredentialsSet isConnected "MyClientID" "robot name" "robot owner" CRIEND 'enabled', 'areCredentialsSet' and 'isConnected' will be True or False.
Implemented in TinyCtrl V980-13-040 and newer CRISTART 1234 CONFIG GetReferencingProgram CRIEND Gets the referencing program configuration. Response: CRISTART 1234 CONFIG ReferencingProgram <program> <afterRefAll> CRIEND See "SetReferencingProgram" for the format of the parameters.
Implemented in TinyCtrl V980-13-040 and newer CRISTART 1234 CONFIG SetReferencingProgram <program> <afterRefAll> CRIEND Sets the referencing program and defines whether the referencing program is run after "reference all". <program> is a program file relative to Data/Programs or "n/a" for no program. <afterRefAll> is true or false.

4.12 Licensing Commands

Available in CPRog: from version V902-12

Available in TinyCtrl: from version V980-12

License information can be queried via the following commands. Installing new licenses is done via SSH.

CRISTART 1234 LICENSE GetInfo CRIEND Requests license information. The following response will be sent: CRISTART 1234 LICENSE Info <valid/invalid> <evaluation period> <date> <owner> CRIEND Evaluation period is the remaining number of seconds that all extended features can be used without license.
CRISTART 1234 LICENSE GetFeatures CRIEND Requests information features that are enabled by the installed license. The following response will be sent: CRISTART 1234 LICENSE Features <list of features> CRIEND <list of features> is a list of strings separated by semicolon. Additional parameters may be added to the entries in future.
CRISTART 1234 LICENSE GetDeviceID CRIEND Requests the device ID that is needed for a license request. The following response will be sent: CRISTART 1234 LICENSE DeviceID <ID> CRIEND <ID> is a SHA256 hash encoded as a hex string

4.13 Mobile Platform commands

Available in CPRog: from version V902-13

Not available in TinyCtrl

Commands for the mobile platform are categorized in the following groups:

- PLTF – general commands
- PLTFMAP – platform map
- PLTFMISSION – platform mission
- SEQPLTF – modifies commands within a mission

Platform commands currently are not final and may change!

4.13.1 PLTF

CRISTART 1234 PLTF ResetPosition <pos x> <pos y> <ori> CRIEND Resets the platform position at the given coordinates (in m) and orientation (in degrees).
--

4.13.2 PLTFMAP

CRISTART 1234 PLTFMAP FileInfo CRIEND Requests the filename of the loaded map. The following response will be sent if a map is loaded: CRISTART 1234 PLTFMAP FileInfo <filename> CRIEND The following response will be sent if no map is loaded:
--

CRISTART 1234 PLTFMAP FileInfo none CRIEND
CRISTART 1234 PLTFMAP OccGrid CRIEND Requests the occlusion grid. The following response will be sent if an occlusion grid is available. Width and height are in pixels, data is a base64 encoded PNG image. Currently the message size for a 200x200 grid is about 2kB, however this may change in future.
CRISTART 1234 PLTFMAP OccGrid <width> <height> <data> CRIEND

4.13.3 PLTFMISSION

CRISTART 1234 PLTFMISSION Start CRIEND Starts or continues a mission, if loaded.
CRISTART 1234 PLTFMISSION Stop CRIEND Stops a mission and robot program (same effect as CMD StopProgram).
CRISTART 1234 PLTFMISSION Pause CRIEND Pauses a mission and robot program (same effect as CMD PauseProgram).
CRISTART 1234 PLTFMISSION Replay <mode> CRIEND Sets the replay mode of the mission: single: Do not repeat mission after it finishes repeat: Repeat mission after it finishes step: Pause after each platform command, do not repeat
CRISTART 1234 PLTFMISSION GetStatus CRIEND Requests the status of the mission. The following response will be sent: CRISTART 1234 PLTFMISSION Status <runstate> <replaymode> <collOverride> <seqState> <missionname> CRIEND Runstate can be one of the following values: NotRunning, Running, Paused Replaymode can be one of the following values: Single, Repeat, Step, CollOverride is the collision override in percent SeqState is the number of the current platform command Missionname is the file name of the mission or none
CRISTART 1234 PLTFMISSION Load <filename> CRIEND Loads the mission from the given filename.
CRISTART 1234 PLTFMISSION Save <filename> CRIEND Saves the mission to the given filename.
CRISTART 1234 PLTFMISSION Delete CRIEND Deletes the mission from memory but not from disk. A Waypoint response will be sent indicating that no commands are loaded (see the following command).
CRISTART 1234 PLTFMISSION GetWaypoint <idx> CRIEND Requests the mission command at the given index. The following response will be sent if the command exists: CRISTART 1234 PLTFMISSION Waypoint <cnt> <idx> <definition> CRIEND If no commands are loaded or if the index is out of range the following response will be sent. In the former case cnt is 0. The command definition depends on the command: MovePos <X> <Y> <speed> MovePosOri <X> <Y> <orientation> <speed> Wait <duration in s> Approach <distance> <speed> Precision <X> <Y> <orientation> <speed> RobotArmCommand <program name> Turn <angle> <speed> The number values can be decimal values (dot '.' as separator). Speed is in percent 0-1.
CRISTART 1234 PLTFMISSION Waypoint <cnt> 0 CRIEND
CRISTART 1234 PLTFMISSION SetWaypoint <idx> <definition> CRIEND Adds a mission command after the specified index. -1 for first position, bigger or equal to the command count for the end.

