

3 High-Speed Ethernet Server Function

3.3 Communication Method

3.3.3.5 Axis Configuration Information Reading Command

Request

Sub header part

<Details>

Command No.	0x74	
Instance	Specify one out of followings <ul style="list-style-type: none"> • 1 to 8 • 11 to 18 • 21 to 44 • 101 to 108 • 111 to 118 	Specify the control group <ul style="list-style-type: none"> 1 : R1 to 8 : R8 ...Robot (pulse value) 11 : B1 to 18 : B8 ...Base (pulse value) 21 : S1 to 44 : S24 ...Station (pulse value) 101 : R1 to 108 : R8 ...Robot (cartesian value) 111 : B1 to 118 : B8 ...Base (cartesian value)
Attribute	Specify one out of followings <ul style="list-style-type: none"> 1: "Axis name" of the first axis 2: "Axis name" of the second axis 3: "Axis name" of the third axis 4: "Axis name" of the fourth axis 5: "Axis name" of the fifth axis 6: "Axis name" of the sixth axis 7: "Axis name" of the seventh axis 8: "Axis name" of the eighth axis 	Specify the data number of axis information. Each axis name is set from Byte 0. "0" is set to nonexistent axis.
Service	<ul style="list-style-type: none"> •Get_Attribute_Single:0x0E •Get_Attribute_All: 0x01 	Specify the accessing method to the data. 0x0E: Read out data of the specified element number. 0x01: Read out data of all the element number. (In this case, specify 0 to the element number.)

Data part

No data part

Answer

Sub header part

<Details>

Status	Respond by one in the followings <ul style="list-style-type: none"> • 0x00 :respond normally • Other than 0x00 : respond abnormally 	
Added status size	<ul style="list-style-type: none"> • 0: not specified • 1: 1 WORD • 2: 2 WORD 	"1" indicates 1 WORD of added status data, and "2" indicates 2 WORD of added status data.
Added status	The error code specified by the added status size	The error code of 1 WORD exists if the added status code is "1" and that of 2 WORD exists if the code is "2".

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Data part

32bit integer	Byte 0	Byte 1	Byte 2	Byte3	<Details>
1	First coordinate name				"S" (R*: pulse)/"X" (R*/B*: cartesian value)/ "1" (B*/S*: pulse)
2	Second coordinate name				"L" (R*: pulse)/"Y" (R*/B*: cartesian value)/ "2" (B*/S*: pulse)
3	Third coordinate name				"U" (R*: pulse)/"Z" (R*/B*: cartesian value)/ "3" (B*/S*: pulse)
4	Fourth coordinate name				"R" (R*: pulse)/"Rx" (R*: cartesian value)/ "4" (B*/S*: pulse)
5	Fifth coordinate name				"B" (R*: pulse)/"Ry" (R*: cartesian value)/ "5" (B*/S*: pulse)
6	Sixth coordinate name				"T" (R*: pulse)/"Rz" (R*: cartesian value)/ "6" (B*/S*: pulse)
7	Seventh coordinate name				"E" (R*: pulse)/"Rz" (R*: cartesian value)/ "7" (B*/S*: pulse)
8	Eighth coordinate name				

*: Each control group number.

R: Robot (R1 to R8)

S: Station (S1 to s24)

B: Base (B1 to b8)