

```

clear all
close all
clc
set_param('ball_on_plate_simulink','SimulationCommand','start')
sim=remApi('remoteApi');
sim.simxFinish(-1);
clientID=sim.simxStart('127.0.0.1',19999,true,true,5000,5);
if (clientID>-1)
    disp('Connected to remote API server');

    %set_param('ball_on_plate_simulink','SimulationCommand','start')

    %joints
    h=[0,0];
    [r,h(1)]=sim.simxGetObjectHandle(clientID, 'RotateY0',sim.simx_opmode_blocking);
    [r,h(2)]=sim.simxGetObjectHandle(clientID, 'RotateX',sim.simx_opmode_blocking);

    while true

[res,retInts,retFloats,retStrings,retBuffer]=sim.simxCallScriptFunction(clientID,'Cam',sim.sim_scr
ipttype_childscript,'CoordCalc',[],[],[],'',sim.simx_opmode_blocking);
    xcoord=retFloats(1);
    ycoord=retFloats(2);

    set_param('ball_on_plate_simulink/xcoord','Value',num2str(xcoord));
    %pause(0.01);

    set_param('ball_on_plate_simulink/ycoord','Value',num2str(ycoord));
    %pause(0.01);

    thetax=get_param('ball_on_plate_simulink/thetax','RuntimeObject');
    angleX1= (thetax.InputPort(1).Data * 10000)

    thetay=get_param('ball_on_plate_simulink/thetay','RuntimeObject');
    angleY1= (thetay.InputPort(1).Data);

    sim.simxSetJointTargetPosition(clientID,h(2),angleX1,sim.simx_opmode_streaming);
    sim.simxSetJointTargetPosition(clientID,h(1),angleY1,sim.simx_opmode_streaming);

    end
else
    disp('Failed connecting to remote API server');

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end
    sim.delete(); % call the destructor!

disp('Program ended');
```