PC to LCM direct message

You can define new functionality for example motor, actuator, lamp etc.

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
add\\\",\\\"functionalityName\\\":\\\"test_lamp\\\"}\"}"
```

also

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
add\\\",\\\"fName\\\":\\\"test_lamp\\\"}\"}"
```

Response you can see in topic "pcb2f"

```
ros2 topic echo /pcb2f
```

Response will look like this (fID will increase for each functionality):

```
data: '{"fID":8,"EXEC":"OK"}'
```

```
---
```

Commands:

- add
- addPin (pinTypeOutput, pinNumber)
- setOutputByName (outputLevel)
- invertOutput
- getVoltageByName
- getCurrentByName
- getStateByName
- setCurrentLimit (minCurrent,warningCurrent, faultCurrent)
- setOverCurrentIntegralLimit
- setOutputsAsPWM

Example to add new functionality "test_lamp" on output VO_42

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
add\\\",\\\"functionalityName\\\":\\\"test_lamp\\\"}\"}"
```

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
addPin\\\",\\\"functionalityName\\\":\\\"test_lamp\\\",\\\"pinTypeOutput\\\":true,
\\\"pinNumber\\\":49}\"}"
```

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
setOutputByName\\\",\\\"functionalityName\\\":\\\"test_lamp\\\",\\\"
outputLevel\\\":1}\"}"
```

```
ros2 topic pub --once f2pcb std_msgs/msg/String "{\"data\": \"{\\\"cmd\\\":\\\"
setOutputByName\\\",\\\"functionalityName\\\":\\\"test_lamp\\\",\\\"
outputLevel\\\":0}\"}"
```

functionality_cmd-1.pdf
generate_config.pdf
upload_configV3.py
upload_config 1.py
stolz_func_config