

## Loading

Topic	Type	Payload	Description
<i>/tables/connection</i>	<i>Publish</i>	<i>arduinoLoadingTable connected arduinoRollingTable connected arduinoQualityTable connected arduinoColourSensor connected arduinoUnloadingTable connected</i>	<i>Info about connection of the arduinos.</i>
/loading/loopTime	Publish	{timeMillis}	Time of the main loop.
/loading/motorInfo	Publish	isStarted { value } direction {value} speed {value}	Info about motor. isStarted: 0 or 1 direction: l or r speed: (0,255)
/loading/info	Publish	isStarted { value } direction {value} speed {value} loopTime {value} action {value} DoneMsg	Info about table if something was changed. isStarted(motor): 0 or 1 direction: l or r speed: (0,255) loopTime: 0 or 1 action: F or D DoneMsg: " Rolling is done."
/loading/warning	Publish	Some warnings	If something wrong, Arduino sends a msg
/loading/rfidReadProblem	Publish	Msg with info about movement of the material. (a lit bit right or left)	If rfid reader cannot read a tag, this msg will be sent.
/loading/control	Subscribe	{t} – loop time (on/off) {i} – motorInfo {s} – start motor {p} – pause motor {r} – direction right {l} – direction left {number} – speed (0,255)	Extra control of the table. (GodMode)

## Rolling

Topic	Type	Payload	Description
/rolling/loopTime	Publish	{timeMillis}	Time of the main loop.
/rolling/motorInfo	Publish	isStarted { value } isRollingStarted {value} direction {value} rollingDirection {value} speed {value} rollingSpeed {value}	Info about motor. isStarted: 0 or 1 isRollingStarted  0 or 1 direction: l or r rollingDirection: l or r speed: (0,255) rollingSpeed: (0,255)
/ rolling /info	Publish	isStarted { value } isRollingStarted {value} direction {value} rollingDirection {value} speed {value} rollingSpeed {value} loopTime {value} DoneMsg	Info about table if something was changed. isStarted(motor): 0 or 1 direction: l or r speed: (0,255) loopTime: 0 or 1
/ rolling /warning	Publish	Some warnings	If something wrong, Arduino sends a msg
/ rolling /control	Subscribe	{t} – loop time (on/off) {i} – motorInfo {s} – start motor {p} – pause motor {m} – start roll {z} – pause roll {r} – direction right (automatically for roll direction) {l} – direction left (automatically for roll direction) {number} – speed (0,255) (automatically for roll speed)	Extra control of the table. (GodMode)

## Quality

Topic	Type	Payload	Description
/quality/loopTime	Publish	{timeMillis}	Time of the main loop.
/quality/motorInfo	Publish	isStarted {value} direction {value} speed {value}	Info about motor. isStarted: 0 or 1 direction: l or r speed: (0,255)
/quality/info	Publish	isStarted {value} direction {value} speed {value} loopTime {value} DoneMsg	Info about table if something was changed. isStarted(motor): 0 or 1 direction: l or r speed: (0,255) loopTime: 0 or 1
/ quality /warning	Publish	Some warnings	If something wrong, Arduino sends a msg
/ quality /control	Subscribe	{t} – loop time (on/off) {i} – motorInfo {s} – start motor {p} – pause motor {r} – direction right {l} – direction left {number} – speed (0,255)	Extra control of the table. (GodMode)

## ColourSensor

Topic	Type	Payload	Description
/ colourSensor/warning	Publish	Some warnings	If something wrong, Arduino sends a msg

## Unloading

Topic	Type	Payload	Description
/unloading/loopTime	Publish	{timeMillis}	Time of the main loop.
/unloading/motorInfo	Publish	isStarted { value } direction {value} speed {value} TurnedOut {value}	Info about motor. isStarted: 0 or 1 direction: l or r speed: (0,255) TurnedOut: 0 or 1 (position of turnout system [0 is start pos])
/ unloading /info	Publish	isStarted { value } direction {value} speed {value} loopTime {value} TurnedOut {value} DoneMsg	Info about table if something was changed. isStarted(motor): 0 or 1 direction: l or r speed: (0,255) loopTime: 0 or 1 TurnedOut: 0 or 1 (position of turnout system [0 is start pos])
/ unloading /warning	Publish	Some warnings	If something wrong, Arduino sends a msg
/ unloading /control	Subscribe	{t} – loop time (on/off) {i} – motorInfo {s} – start motor {p} – pause motor {r} – direction right {l} – direction left {number} – speed (0,255) {f} – turn out forward {b} – turn out back	Extra control of the table. (GodMode)