

# 1 Single joint control

```
<!-- initialize the program -->
const mycobot = require('mycobot')

const obj = mycobot.connect('COM15',115200)

<!-- set the angle of single robot arm mycobot.sendAngle(robot arm ID, angle
value, the running speed at which the robot arm adjusts the angle)-->
<!-- Note:When setting the value to change the angle, pay attention to the number
of robot arm joints. if the number is 4, input 1-4; if the number is 6, input 1-
6; otherwise an error is reported.-->
<!-- For setting of the angles of four-axis and six-axis robot arms, see Digram
1-3 -->

obj.write(mycobot.sendAngle(1,110,10))

<!-- set the coordinate of a single robot arm mycobot.sendCoord(robot armID,
coordinate value, the the movement speed at which the robot arm adjusts the
coordinate)-->

obj.write(mycobot.sendCoord(1,20,10))
```

# 2 Multi-joint control

**Note: When operating multiple joints, fill in the parameters corresponding to the number of joints of the robot arm.**

```
<!-- initialize the program -->
const mycobot = require('mycobot')

const obj = mycobot.connect('COM15',115200)

<!-- set the angle of the multi-joint robot arm mycobot.sendAngles([angle of
joint 1, angle of joint 2, angle of joint 3, angle of joint 4, angle of joint 5,
angle of joint 6], joint running speed) -->
<!-- set the coordinate of the multi-joint robot arm
mycobot.sendCoords([coordinate of joint 1, coordinate of joint 2, coordinate of
joint 3, coordinate of joint 4, coordinate of joint 5, coordinate of joint 6],
joint running speed) -->

obj.write(mycobot.sendCoords([22.5,12,-22,45],20))
```

# 3 Standard parameters of angles and coordinates of four-axis and six-axis robot arms

- Four-axis robot arm

Joint ID	Limited Values
1	-160~160
2	0~90
3	-90~45
4	Unlimited Values

- Six-axis robot arm

Joint ID	Limited Values
1	-170~170
2	-170~170
3	-170~170
4	-170~170
5	-170~170
6	Unlimited Values