The Use of Sucking Pump

Preparation

M5Stack series: Make sure robot is connected with PC.

Other series: Make sure the robot is in normal status.

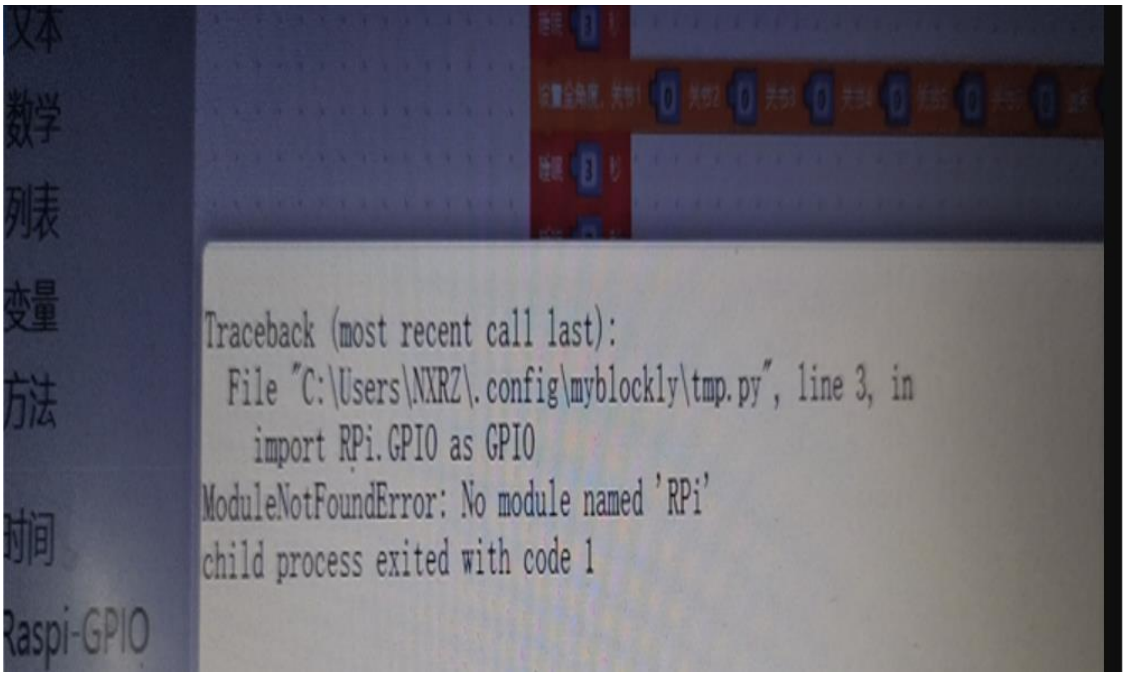
This section takes myPalletizer 260 M5Stack as an example to explain the use of suction pump.

Purpose for this section

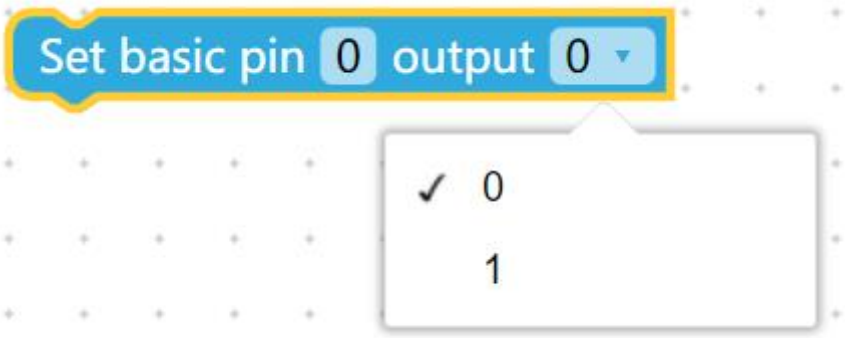
This section introduces instructions for using sucking pump.

Introduction to API

> **Notice:** M5Stack version is unable to use the blocks belonging to Raspberry Pi version. Otherwise, the system may report an error.



- `Set Basic pin () output ()` (for M5Stack version)



- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:

    - `pin ()` : the numerical part of the numbers marked at the bottom of the equipment
    - `output ()`: `0` means setting to the running state, and `1` means setting to the stop state
- Function: set the working state of the preset bottom pin
- `get_basic_input(pin_no)` (for M5Stack version)

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
    - `pin()`: the numerical part of the numbers marked at the bottom of the equipment
- Function: get the working state of the bottom pin number
- `set mode ()` (for Raspberry Pi version)

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
    - `mode()` : "BCM" or "BOARD"
- Function: set Raspberry Pi GPIO Pin Mode
- `set pin() mode()` (for Raspberry Pi version)

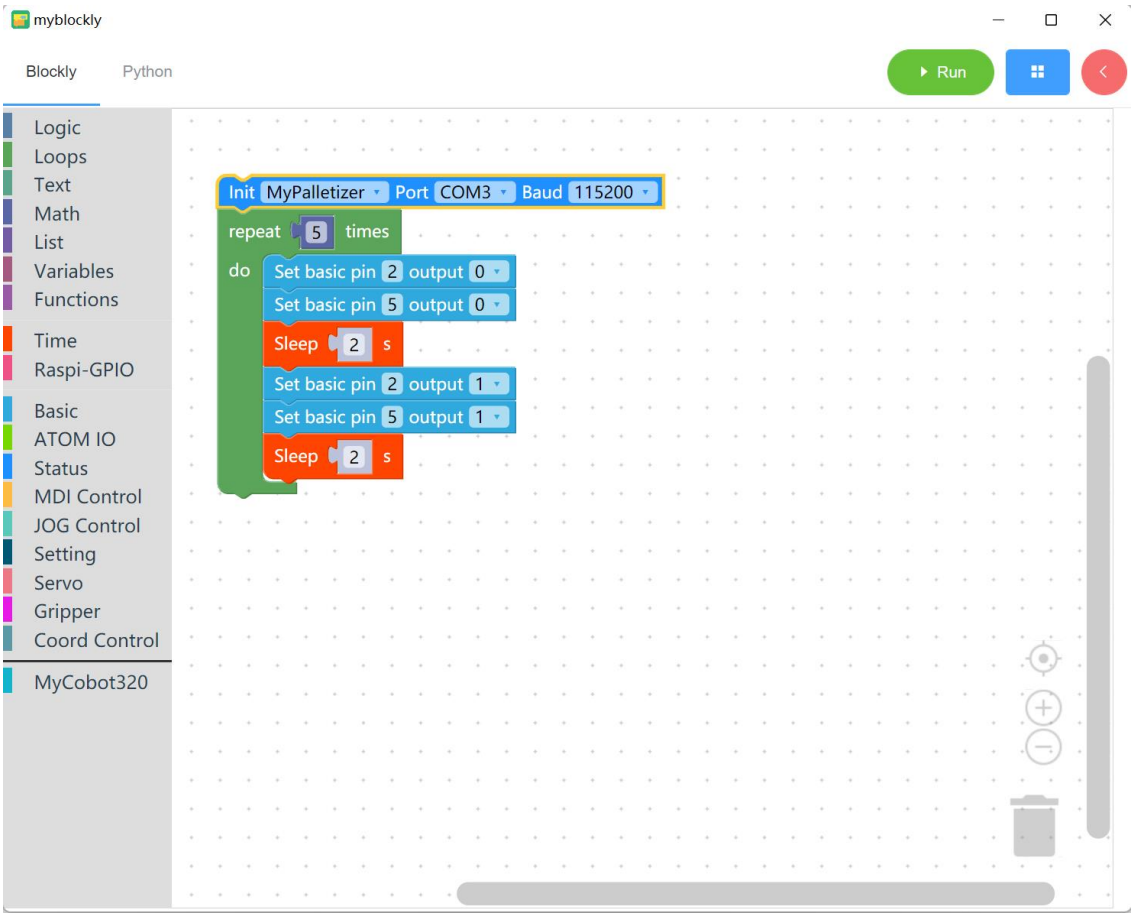
- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
    - `pin ()` : the numerical part of the numbers marked at the bottom of the equipment
    - `mode ()`: `in` means signal import, and `OUT` means signal output
- Function: set signal of the preset bottom pin
- `set pin() output()` (for Raspberry Pi version)

- Applicable to myCobot 280 series, mechArm 270 series, and myPalletizer 260 series
- Parameter:
    - `pin()` : the numerical part of the numbers marked at the bottom of the equipment
    - `output()` : `HIGH` means high level of sucking pump working state, and `LOW` means low level of sucking pump working state

- Function: set the working state of bottom pin to high level or low level

Simple Demo

- Program for display:



- Motion:

  Sucking pump vibrates and work to suck objects,

  after 2 seconds, sucking pump put objects down,

  after 2 seconds, it vibrates again. The whole process loops 5 times.