

Case 1

```
<!-- Initialization procedure -->
const mycobot = require('mycobot')
const obj = mycobot.connect('COM15',115200)

<!-- Suppose a four axis manipulator is connected -->
const name = "myPallizer"
<!-- If the connected equipment is a six axis manipulator -->
if(name == "myCobot"){
    <!-- Sets the angle of each of the six joints -->
    obj.write(mycobot.sendAngles([-1.49,115,-153.45,30,-33.42,137.9],80))
    <!-- And judge whether the coordinate is reached -->
    if(obj.write(mycobot.isInPosition([-1.49,115,-153.45,30,-33.42,137.9],0)) ==
1){
        <!-- Resume manipulator movement -->
        obj.write(mycobot.programResume())
        <!-- wait 0.5 seconds -->
        setTimeout(() =>{
            <!-- Pause the manipulator movement -->
            obj.write(mycobot.programPause())
        },500)
    }
}else{
    <!-- Sets the angle of each of the four joints -->
    obj.write(mycobot.sendAngles([-1.49,45,-23,30],80))
    <!-- Sets the color of the atom indicator -->
    obj.write(mycobot.setColor(0,0,50))
    <!-- wait 0.7 seconds -->
    setTimeout(() =>{
        <!-- Set the angles of the four joints again -->
        obj.write(mycobot.sendAngles([-1.49,60,11,30],80))
        <!-- Sets the color of the atom indicator -->
        obj.write(mycobot.setColor(0,50,0))
    },700)
}
}
```

Case 2

```
<!-- Initialization procedure -->
const mycobot = require('mycobot')
const obj = mycobot.connect('COM15',115200)

<!-- Gets the angle of all current joints -->
const botData = obj.write(mycobot.getAngles())
<!-- Outputs the angle of all current joints -->
console.log(botdata)
<!-- Sets the angle of all current joints -->
obj.write(mycobot.sendAngles([0,0,0,0],50))
<!-- Print whether the robot arm currently reaches this position -->
```

```
console.log(obj.write(mycobot.isInPosition([0,0,0,0,0,0],0)) == 1)

<!-- wait for 3 seconds -->
setTimeout(() =>{
  <!-- Sets the angle of the first joint -->
  obj.write(mycobot.sendAngle(1,90,50))
},3000)

<!-- wait two seconds -->
setTimeout(() =>{
  <!-- Set the second joint angle to 50 degrees -->
  obj.write(mycobot.sendAngle(2,50,50))
},2000)
<!-- wait 1.5 seconds -->
setTimeout(() =>{
  <!-- Set the joint triangulation to 50 degrees -->
  obj.write(mycobot.sendAngle(3,-50,50))
},1500)
<!-- wait 1.5 seconds -->
setTimeout(() =>{
  <!-- Set all joint angles of the manipulator -->
  obj.write(mycobot.sendAngles([88.68, -138.51, 155.65, -128.05, -9.93,
-15.29],50))
},1500)
<!-- wait for 2.5 seconds -->
setTimeout(() =>{
  <!-- Set the manipulator to free mode -->
  obj.write(mycobot.releaseAllServos())
},2500)
```