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%Initialize API

sim=remApi('remoteApi');

% using the prototype file (remoteApiProto.m)

sim.simxFinish(-1);

% just in case, close all opened connections

clientID=sim.simxStart('127.0.0.1',19999,true,true,5000,5);

if (clientID>-1)
end

disp('Connected to remote API server');

sim.simxGetStringSignal(clientID,'distance',sim.simx_opmode_streaming);

set_param('ballclmod', 'SimulationCommand', 'start')

    while(1) % In this while loop, we will have the communication

        [errorCode,r_mat]=sim.simxGetStringSignal(clientID,'distance',sim.✓
simx_opmode_buffer);

        %%if errorCode is not vrep.simx_return_ok, this does not mean there is an error:

        %%it could be that the first streamed values have not yet arrived, or that the✓
signal

        %%is empty/non-existent

        set_param('ballclmod/Constant','Value',num2str(r_mat)); %ballclmod is the✓
model file and Constant is the block's name, r_mat is the variable to send.

        pause(.01);

        theta = get_param('ballclmod/To Workspace','RuntimeObject'); % We receive the✓
sensor data from Simulink model ballclmod and To Workspace block via RuntimeObject

        theta.InputPort(1).Data;✓
% Receive the data

    end
```