typedef struct Walk\_Knead\_Knock\_Motor\_Struct\_Auto

{

//1st byte

unsigned char nSubFunction ;

unsigned nWalkMotorLocateMethod:4 ;

//2nd byte

unsigned short nWalkMotorLocateParam; //长行程

//3rd byte

unsigned nKneadMotorState:4 ;

unsigned nKneadMotorCycles:4 ;

//4th byte(KNOCK\_STOP,KNOCK\_RUN\_WIDTH,KNOCK\_RUN,KNOCK\_RUN\_STOP,KNOCK\_RUN\_MUSIC)

//Only 4 states for auto mode

unsigned nKnockMotorState:2 ;

unsigned nKnockMotorRunTime:6 ;//敲打持续的时间

//5th byte

unsigned nKnockMotorStopTime:5 ;//敲打停顿的时间

unsigned nAxisMotorPosition ;//敲打停顿的时间

unsigned nKneadKnockSpeed:3 ;

} WALK\_KNEAD\_KNOCK\_MOTOR\_STRUCT\_AUTO ;

/\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*/

typedef struct Walk\_Knead\_Knock\_Motor\_Struct\_Manual

{

//子功能索引(用于显示)

//KNEAD,KNOCK,PRESS,WAVELET,PREPARE

unsigned char nSubFunction ;

//行走电机定位方式

//0:WALK\_LOCATE\_ABSULATE:由绝对坐标决定

//1:WALK\_LOCATE\_SHOULDER:由肩部位置决定

//2:WALK\_LOCATE\_TOP:由上端行程开关决定

//3:WALK\_LOCATE\_SHOULDER\_OR\_ABSULATE:由肩部位置和绝对坐标中的较小者决定

//4:WALK\_LOCATE\_PARK:停留在当前位置

unsigned char nWalkMotorLocateMethod ;

//行走电机定位的绝对坐标或在PARK时的停顿时间

unsigned short nWalkMotorLocateParam ; //长行程

//揉捏电机描述(包含了结束条件)

//KNEAD\_STOP 0 //按摩臂停留在随机位置

//KNEAD\_STOP\_AT\_MIN 1 //按摩臂停留在窄的位置

//KNEAD\_STOP\_AT\_MED 2 //按摩臂停留在中的位置

//KNEAD\_STOP\_AT\_MAX 3 //按摩臂停留在宽的位置

//KNEAD\_RUN 4 //按摩臂顺时钟方向揉捏

//KNEAD\_RUN\_STOP 5 //按摩臂n圈后停留在随机位置

//KNEAD\_RUN\_STOP\_AT\_MIN 6 //按摩臂n圈后停留在窄的位置

//KNEAD\_RUN\_STOP\_AT\_MED 7 //按摩臂n圈后停留在中的位置

//KNEAD\_RUN\_STOP\_AT\_MAX 8 //按摩臂n圈后停留在宽的位置

unsigned char nKneadMotorState ;

//揉捏圈数

unsigned char nKneadMotorCycles ;

//揉捏方向 RT8600

// unsigned char nKneadMotorPhase ;

//敲打电机要达到的状态

//KNOCK\_STOP/KNOCK\_RUN\_WIDTH/KNOCK\_RUN/KNOCK\_RUN\_STOP

unsigned char nKnockMotorState ;

unsigned char nKnockMotorRunTime ;//敲打持续的时间

unsigned char nKnockMotorStopTime ;//敲打停顿的时间

//揉捏与敲打的速度

//SPEED\_0,AXIS\_5,SPEED\_2,AXIS\_5,SPEED\_3,AXIS\_5,SPEED\_4

unsigned char nKneadKnockSpeed ;

unsigned char \_3D\_Position;

unsigned char \_3D\_Speed;

} WALK\_KNEAD\_KNOCK\_MOTOR\_STRUCT\_MANUAL ;

bBackAutoModeInit

bBackManualModeInit

bWalkMotorInProcess

bKneadMotorInProcess

bKnockMotorInProcess

bGetNextActionStep