

O (PLC) -> T (Robot)

Bit	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	Group
	SSM   Reserved																														Robot	
32	Speed slider fraction (float)																														Robot	
64	Standard digital output mask							Configurable digital output mask							Standard digital outputs							Configurable digital outputs							Outputs			
96	AOM			Reserved				AOT			Reserved				TDOM			Reserved				TDO			Reserved							
128	Standard analog output 0 (float) [0..1]																														Outputs	
160	Standard analog output 1 (float) [0..1]																															
192	Bit input registers 0 - 31																														Bit registers	
224	Bit input registers 32 - 63																															
256	Int input register 0 (int)																														Int registers	
288	Int input register 1 (int)																															
320	Int input register 2 (int)																															
352	Int input register 3 (int)																															
384	Int input register 4 (int)																															
416	Int input register 5 (int)																															
448	Int input register 6 (int)																															
480	Int input register 7 (int)																															
512	Int input register 8 (int)																															
544	Int input register 9 (int)																															
576	Int input register 10 (int)																															
608	Int input register 11 (int)																															
640	Int input register 12 (int)																															
672	Int input register 13 (int)																															
704	Int input register 14 (int)																															
736	Int input register 15 (int)																															
768	Int input register 16 (int)																															
800	Int input register 17 (int)																															
832	Int input register 18 (int)																															
864	Int input register 19 (int)																															
896	Int input register 20 (int)																															
928	Int input register 21 (int)																															
960	Int input register 22 (int)																															
992	Int input register 23 (int)																															
1024	Float input register 0 (float)																														Float registers	
1056	Float input register 1 (float)																															
1088	Float input register 2 (float)																															
1120	Float input register 3 (float)																															
1152	Float input register 4 (float)																															
1184	Float input register 5 (float)																															
1216	Float input register 6 (float)																															
1248	Float input register 7 (float)																															
1280	Float input register 8 (float)																															

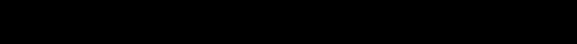
Bit	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	Group
1312	Float input register 9 (float)																														Float registers	
1344	Float input register 10 (float)																															
1376	Float input register 11 (float)																															
1408	Float input register 12 (float)																															
1440	Float input register 13 (float)																															
1472	Float input register 14 (float)																															
1504	Float input register 15 (float)																															
1536	Float input register 16 (float)																															
1568	Float input register 17 (float)																															
1600	Float input register 18 (float)																															
1632	Float input register 19 (float)																															
1664	Float input register 20 (float)																															
1696	Float input register 21 (float)																															
1728	Float input register 22 (float)																															
1760	Float input register 23 (float)																															

T (Robot) -> O (PLC)

Bit	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	Group
	Controller major version (uint)							Controller minor version (uint)							Reserved																	
32	Robot mode (uint)							Real time machine seconds (uint)							Real time machine milliseconds (uint)																	
64	Real time machine minutes (uint)							Real time machine hours (uint)							Real time machine days (uint)																	
96	Robot current (float) [A]																															
128	PW	PR	TB	PB	Reserved																											
160	Speed slider fraction (float)																															
192	Safety mode (uint)							Reserved																								
224	NO	RD	PS	RC	SS	SES	RES	ES	VL	FT	ST	Reserved																				
256	Standard digital inputs							Configurable digital inputs							Standard digital outputs							Configurable digital outputs										
288	Analog I/O Types			Reserved																												
320	Standard analog input 0 (float) [A or V]																															
352	Standard analog input 1 (float) [A or V]																															
384	Standard analog output 0 (float) [A or V]																															
416	Standard analog output 1 (float) [A or V]																															
448	I/O current (float) [A]																															
480	Euromap67 input bits																															
512	Euromap67 output bits																															
544	Euromap67 24V voltage (float) [V]																															
576	Euromap67 24V current (float) [A]																															
608	Tool mode (uint)							Reserved																								
640	TDI	Reserved					TDO	Reserved					TAIT	Reserved																		
672	Tool analog input 0 (float) [A or V]																															
704	Tool analog input 1 (float) [A or V]																															
736	Tool output voltage (float) [V]																															
768	Tool current (float) [A]																															
800	Joint 0 position (float) [rad]																															
832	Joint 1 position (float) [rad]																															
864	Joint 2 position (float) [rad]																															
896	Joint 3 position (float) [rad]																															
928	Joint 4 position (float) [rad]																															
960	Joint 5 position (float) [rad]																															
992	Joint 0 velocity (float) [rad/s]																															
1024	Joint 1 velocity (float) [rad/s]																															
1056	Joint 2 velocity (float) [rad/s]																															
1088	Joint 3 velocity (float) [rad/s]																															
1120	Joint 4 velocity (float) [rad/s]																															
1152	Joint 5 velocity (float) [rad/s]																															
1184	Joint 0 current (float) [A]																															
1216	Joint 1 current (float) [A]																															
1248	Joint 2 current (float) [A]																															
1280	Joint 3 current (float) [A]																															

Bit	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25	26	27	28	29	30	31	Group
1312													Joint 4 current (float) [A]															Joints				
1344													Joint 5 current (float) [A]																			
1376													Joint 0 temperature (float) [°C]																			
1408													Joint 1 temperature (float) [°C]																			
1440													Joint 2 temperature (float) [°C]																			
1472													Joint 3 temperature (float) [°C]																			
1504													Joint 4 temperature (float) [°C]																			
1536													Joint 5 temperature (float) [°C]																			
1568	Joint 0 mode (uint)					Joint 1 mode (uint)					Joint 2 mode (uint)					Joint 3 mode (uint)																
1600	Joint 4 mode (uint)					Joint 5 mode (uint)					Reserved																					
1632													TCP position X (float) [m]															TCP				
1664													TCP position Y (float) [m]																			
1696													TCP position Z (float) [m]																			
1728													TCP position RX (float)																			
1760													TCP position RY (float)																			
1792													TCP position RZ (float)																			
1824													TCP velocity X (float) [m/s]																			
1856													TCP velocity Y (float) [m/s]																			
1888													TCP velocity Z (float) [m/s]																			
1920													TCP velocity RX (float)																			
1952													TCP velocity RY (float)																			
1984													TCP velocity RZ (float)																			
2016													TCP force X (float) [N]																			
2048													TCP force Y (float) [N]																			
2080													TCP force Z (float) [N]																			
2112													TCP torque X (float) [N.m]																			
2144													TCP torque Y (float) [N.m]																			
2176													TCP torque Z (float) [N.m]																			
2208													TCP force scalar (float) [N]																			
2240													Bit output registers 0 - 31															Bit registers				
2272													Bit output registers 32 - 63																			
2304													Int output register 0 (int)															Int registers				
2336													Int output register 1 (int)																			
2368													Int output register 2 (int)																			
2400													Int output register 3 (int)																			
2432													Int output register 4 (int)																			
2464													Int output register 5 (int)																			
2496													Int output register 6 (int)																			
2528													Int output register 7 (int)																			
2560													Int output register 8 (int)																			
2592													Int output register 9 (int)																			
2624													Int output register 10 (int)																			





AOM	Analog output mask
AOT	Analog output types
ES	Is emergency stopped
FT	Is fault
NO	Is normal mode
PB	Is power button pressed
PR	Is program running
PS	Is protective stopped
PW	Is power on
RC	Is recovery mode
RD	Is reduced mode
RES	Is robot emergency stopped
SES	Is system emergency stopped
SS	Is safeguard stopped
SSM	Speed slider fraction mask
ST	Is stopped due to safety
TAIT	Tool analog input types
TB	Is teach button pressed
TDI	Tool digital inputs
TDO	Tool digital outputs
TDOM	Tool digital output mask
VL	Is violation