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KYT – 26XX DLL Manual

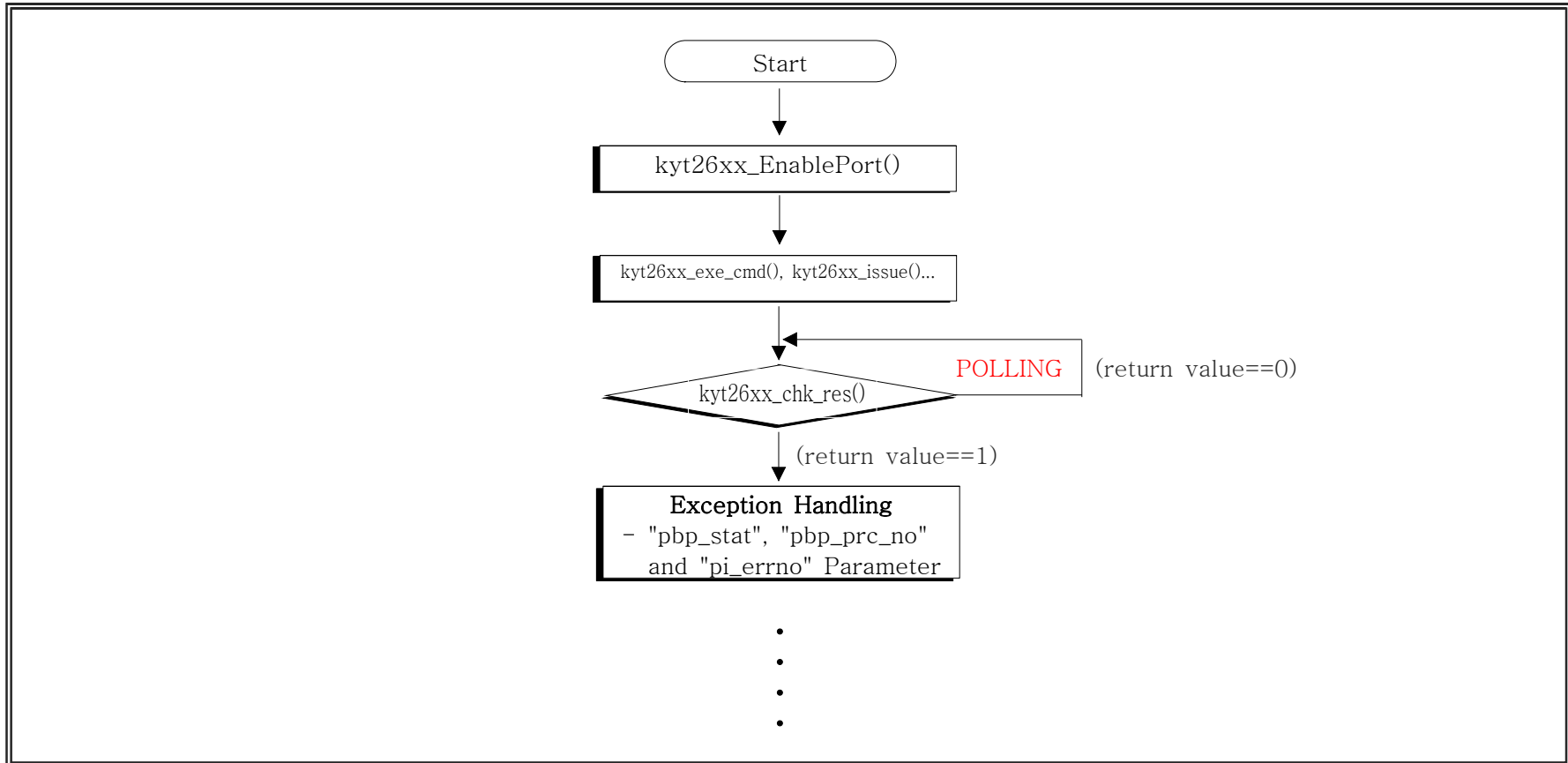
REVISION HISTORY

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|-------|-----------|---------------|------|------|
| 1 | 2005.7.15 | First edition | 1.00 | 11 |
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\$. "kyt_26XX.dll" Library

- Library for Windows NT4.0/2000/XP and Windows 98/Millennium.
- Notice: BYTE==unsigned char, UINT==unsigned int.



- Flow Chart -

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=====

@. kyt26xx_EnablePort()

- Set the serial port to communicate with the terminal.

* PROTOTYPE

- BOOL kyt26xx_EnablePort(char* port, BYTE size, BYTE parity, BYTE stopbit, DWORD baudrate, BYTE control);

* PARAMETERS(Refer to "struct _DCB" in the MSDN.)

- port : ex) "COM1", "COM2", ...
- size : Number of bits/byte, 4~8.
- parity : 0~4=None,Odd,Even,Mark,Space.
- stopbit : 0,1,2 = 1, 1.5, 2.
- baudrate : Baud rate at which running.
- control : 0,1,2,3 = None, XOn/XOff, RTS/CTS, Both.

* RETURN

- Normal: 1
- Error : 0

* REMARKS

- e.g) kyt26xx_EnablePort("COM1", 8, 0, 0, 38400, 0);
- =====

@. kyt26xx_DisablePort()

- Close the serial port to communicate with the terminal.

* PROTOTYPE

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```

        - BOOL kyt26xx_DisablePort();
* PARAMETERS : void
* RETURN      :
    - Normal: 1
    - Error  : 0
=====

```

```

@. kyt26xx_exe_cmd()
    - Transmit the command at the terminal.

```

```

* PROTOTYPE
    - kyt26xx_exe_cmd(BYTE pb_cmd);
* PARAMETERS : Refer to the spec.
    - pb_cmd
        . pb_cmd==0x30: Error Clear.
        . pb_cmd==0x31: Status Request
        . pb_cmd==0x40: Stacker #1 Out
        . pb_cmd==0x41: Stacker #2 Out
        . pb_cmd==0x43: Capture
        . pb_cmd==0x44: Feed In
        . pb_cmd==0x45: Feed Out
        . pb_cmd==0x46: Stop
        . pb_cmd==0x4d: Feed Out (Solenoid)
        . pb_cmd==0x51: Set the Baud rate to 19200 BPS.
        . pb_cmd==0x52: Set the Baud rate to 38400(default) BPS.
        . pb_cmd==0x60: Firmware Version.

```

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* RETURN

- 0 : Parameter Error.
- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

* REMARKS

- It retry 3 time to the automatic when a communication obstacle happens.
- This function can execute all command that is written on the Spec.

=====

@. kyt26xx_chk_res()

- Check finishing the execution about the request command. And read the result values about the request command.

* PROTOTYPE

- int kyt26xx_chk_res(unsigned char *pbp_stat, unsigned char * pbp_prc_no, int *pi_errno);

* PARAMETERS

- pbp_stat: The Pointer of the buffer to take the status value(3BYTE) of the terminal.
 - . If the command is "0x60"(Indicate Firmware Version) : Firmware Version information
 - . Other command : Status value of the terminal.(Refer to the spec)
- pbp_prc_no: The variable for save the sequence number of the request command to process.(1 byte)
- pi_errno
 - . Normal: 0
 - . Error : etc(Refer to the Error Code List.)

* RETURN

- 0: Don't finish the processing.
- 1: Finish the processing.

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@. kyt26xx_exe_stop()

- Stop process about request command.

* PROTOTYPE

- void kyt26xx_exe_stop()

* PARAMETERS : void

* RETURN : void

* REMARKS

- If you must stop the execution because of the time is delayed.
Call exe_stop() function.

=====

@. kyt26xx_call_src_ver()

- Display source version of the dll program in the Message Box.

* PROTOTYPE

- void kyt26xx_call_src_ver()

* PARAMETERS : void

* RETURN : void

=====

@. kyt26xx_clr()

- Error Clear.

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* PROTOTYPE

- int kyt26xx_clr();

* PARAMETERS : void

* RETURN

- 0 : Parameter Error.

- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

=====

@. kyt26xx_rqt()

- Status Request.

* PROTOTYPE

- int kyt26xx_rqt();

* PARAMETERS : void

* RETURN

- 0 : Parameter Error.

- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

=====

@. kyt26xx_issue()

- Issue the card.

* PROTOTYPE

- int kyt26xx_issue(BYTE pb_stk);

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* PARAMETERS

- pb_stk==1: Issue cards piled up at Stacker #1.
- pb_stk==2: Issue cards piled up at Stacker #2.
- pb_stk==3: Issue the Jammed card by using solenoid.

* RETURN

- 0 : Parameter Error.
- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

=====

@. kyt26xx_set_baudrate()

- Set the Baud rate.

* PROTOTYPE

- int kyt26xx_set_baudrate(BYTE pb_pm);

* PARAMETERS

- pb_pm==0x51: 19200 BPS
- pb_pm==0x52: 38400 BPS (Default)

* RETURN

- 0 : Parameter Error.
- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

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@. kyt26xx_card_capture()

- Make Motor #3 run backward to take card back to Bin box.

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* PROTOTYPE

- int kyt26xx_card_capture();

* PARAMETERS: void

* RETURN

- 0 : Parameter Error.

- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

=====

@. kyt26xx_fw_version()

- Check the Firmware Version.

* PROTOTYPE

- int kyt26xx_fw_version();

* PARAMETERS: void

* RETURN

- 0 : Parameter Error.

- 1 ~ 255: The Sequence number about that request(It is utilized to confirm whether it is the result about request when you read the result.)

=====

%. Notice(Refer to the spec)

- All command send "Status Request Command" to the automatic for busy flag inspection.(Except kyt26xx_set_baudrate() Function)

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\$. Error Code List

| | |
|-----|-----------------------------|
| 1 | : No ACK Error |
| 2 | : TIMEOUT Error |
| 3 | : Negative Data error |
| 102 | : Force termination error |
| 106 | : Received data frame error |
| 107 | : Received data BCC error |
| 108 | : Data Transmission error |

\$. Implement the Manager Program.

1.Open and set the serial port by call kyt26xx_EnablePort() function in“kyt_20XX.dll”.

2.Call kyt26xx_rqt(), kyt26xx_issue(),... function according to the deed to do.

The Returned value(pbp_prc_no) in an each function (kyt26xx_exe_cmd(), kyt26xx_issue() ...) is the sequence number about that request command.

It is utilized to confirm whether it is the result about the request when you read the result of the request command.

3. For confirm the result about the request. First you check finishing the execution

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about the request by kyt26xx_chk_res() function. if that finished the execution. Process the result values.

4.If you must stop the execution because of the time is delayed. Call kyt26xx_exe_stop() function.

5.Call kyt26xx_DisablePort() function if you close the serial port.

6. If you changes the setup of the serial port. call kyt26xx_EnablePort() function again.

But you must call kyt26xx_DisablePort() function for close the existing serial port before call kyt26xx_EnablePort() function.