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System Overview
Chapter 1 System Overview

1.1 Introduction

Standalone Data Acquisition and Control System

As the growth of PC-based technology, Advantech PC-based Programmable Controllers have been widely applied in variety of industrial automation applications. Shrunk from the original ADAM-5510 series controller, the ADAM-4500 Series Controller is a new series of stand-alone programmable communication controller. It does not only support high memory capacity, user-friendly configuration tool, rich serial communication interfaces, but also support Ethernet port available and original libraries on specific models. Applying the ADAM-4500 Series Controller, the C programmers would be able to handle any complex task easily.

The ADAM-4500 Series Controller is a compact-sized Ethernet-enabled communication controller under x-86 CPU architecture. It supports not only Ethernet interface but also 4 serial ports, which lets ADAM-4500 Series Controller be very suitable for industrial communication and control applications. The Ethernet-enabled features include built-in HTTP Server, FTP Server and E-mail functions. The modularized I/O design provides high flexibility for versatile application requirements. ADAM-4500 Series Controller also supports rich Modbus function libraries including Modbus/RTU (Master and Slave) and Modbus/TCP (Server and Client) function libraries.

The ADAM-4500 Series Controller includes following models:

- **ADAM-4501** Ethernet-Enabled Communication Controller with 8 DI/O
- **ADAM-4501D** Ethernet-Enabled Communication Controller with 8 DI/O and LED Display
- **ADAM-4502** Ethernet-Enabled Communication Controller with 2-ch AI/O and 4-ch DI/O

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Chapter 1 System Overview

1.2 Features

The system of ADAM-4500 Series Controller consists of two major components: the main unit and I/O modules. The main unit includes the communication ports, CPU ... and so on. The I/O Module of ADAM-4501/4501D includes the 8 digital I/O channels and the ADAM-4502 includes 2 analog I/O and 4 digital I/O. Besides, the ADAM-4501D also includes 7-segment display to show needed information.

1.2.1 Control flexibility with C programming

The ADAM-4500 Series Controller includes an 80188 CPU and a built-in ROM-DOS operating system. It can be used in a way similar to how one uses an x86 PC in the office. Programmers in C can write and compile applications in Borland C 3.0 and download to the ADAM-4500 Series Controller. Given the prevalence of C language programming tools, this is a distinct advantage for many users and can result in a very short learning curve and very modest training expense requirements.

1.2.2 RS-232/485 communication ability

The ADAM-4500 Series Controller has four serial communication ports, giving it excellent communication abilities. This facilitates its ability to control networked devices. The communication ports of different models are listed as below table.

|------------------|--------------------------------|--------------|--------------|----------------------|

Table 1-1 Communication Ports of ADAM-4500 Series Controller

ADAM-4500 Series COM1 is a dedicated RS-232 port, COM2 and COM3 are dedicated RS-485 port, and the fourth communication port is shared by COM4 and Programming port. It is a selectable port by using jumper.
These four ports allowed the ADAM-4500 Series to satisfy diverse communication and integration demands. Programming port is for downloading or transferring executable programs from a host PC to ADAM-4500 Series Controller. It can also be used as an RS-485 communication port (Refer to section 2.2.1 to see how to configure COM4 as Programming port or standard RS-485 communication port). Please refer to following figure to check the location of COM ports.

Figure 1-1 ADAM-4501 Communication Ports
1.2.3 Versatile Protocols of Communication Function Libraries

The communication protocol of the ADAM-4500 Series Controller is user-defined and there are library functions of MODBUS/RTU protocol and MODBUS/TCP protocol available for users. Of course, users can implement ASCII-based command and response protocol by themselves. The function libraries include the following protocols.

- MODBUS/RTU Master Function for connecting to remote I/O modules via RS-485 port
- MODBUS/RTU Slave Function for connecting to HMI/SCADA software via RS-485 port
- MODBUS/TCP Server Function for connecting to HMI/SCADA software via Ethernet port.
- MODBUS/TCP Client Function for connecting to Ethernet-enabled remote I/O modules via Ethernet port.

1.2.4 Built-in ROM and RAM disk for programming

The ADAM-4500 Series Controller has built-in Flash Memory and SRAM for file downloading, system operation and data storage. It provides 1MB file system (960 KB free for users to download programs). There are also 640KB SRAM to provide the memory needed for efficient application operation and file transfer. Moreover, users are allowed to decide the battery backup memory size up to 384KB in the SRAM.

1.2.5 Built-in real-time clock and watchdog timer

The micro-controller also includes a real-time clock and watchdog timer. The real-time clock records events while they occur. The watchdog timer is designed to automatically reset the microprocessor if the system fails. This feature greatly reduces the level of maintenance required and makes the ADAM-4500 Series Controller ideal for use in applications which required a high level of system stability.
1.2.6 Built-in Ethernet Port

The Ethernet port on ADAM-4500 Series Controller can perform powerful function as following:

- FTP Server and Client Function
- Web Server Function
- Send Mail Function
- TCP and UDP Connection by Sockets
Chapter 1 System Overview

1.3 ADAM-4500 Series Controllers Specification

1.3.1 System

- CPU: 16-bit microprocessor
- Memory:
  - 1.5MB Flash memory
    - 256KB system Disk (Drive C: Read Only)
    - 256KB flash memory (Accessed by Function LIB)
    - 1024KB file system, 960KB for user applications (Drive D: Read/Write)
  - 640KB SRAM
    - up to 384KB with battery backup (Accessed by Function LIB)
- Operating System: ROM-DOS (MS-DOS 6.22 Compatible)
- Real-time Clock: yes
- Watchdog Timer: yes
- RS-232 interface: COM1
- RS-485 interface: COM2, COM3
- RS-232/485 interface: Programming Port & COM4 (Select by jumper setting)
- LAN port x 1: 10/100Base-T
- On-board I/O Capacity:

Analog Input (ADAM-4502 only)
  Channels: 1
  Input Type: mV, V, mA
  Input Range: ±150 mV, ±500 mV, ±1 V, ±2.5V, ±5 V, ±10V, ±20 mA
  Resolution: 16-bit
  Sampling rate: 100 Sample/second
  Isolation Voltage: 1000 VDC

Analog Output (ADAM-4502 only)
  Channels: 1
  Output Type: V, mA
  Output Range: 0 ~ 10 V, 0 ~ 20 mA
  Slew Rate: 1 V/μs
  Isolation Voltage: 1000 VDC
  Accuracy: 1% of FSR for current output
  1% of FSR for voltage output
Chapter 1 System Overview

Digital Input 4 Channels (ADAM-4502 only has 2 channels)
- **Dry Contact:**
  - Logic level 0: Close to GND
  - Logic level 1: Open
- **Wet Contact:**
  - Logic level 0: +2 V max.
  - Logic level 1: 4 V ~ 30 V

Digital Output 4 Channels (ADAM-4502 only has 2 channels)
- Open Collector to +40 V, 200 mA (maximum load)

1.3.2 RS-232 interface (COM1)
- Signals: TxD, RxD, RTS, CTS, DTR, DSR, DCD, RI, GND
- Mode: Asynchronous full duplex, point to point
- Connector: DB-9 pin
- Transmission speed: Up to 115.2 Kbps
- Max transmission distance: 50 feet (15.2 m)

1.3.3 RS-485 interface (COM2 & COM3)
- Signals: DATA+, DATA-
- Mode: Half duplex, multi-drop
- Connector: Screw terminal
- Transmission speed: Up to 115.2 Kbps
- Max transmission distance: 4000 feet (1220 m)

1.3.4 RS-485/232 interface (COM4 and programming port)
- RS-232/485 Mode Selectable (Select by jumper setting)
- **RS-232 Mode (Programming port):** Full duplex, point to point
  - Signals: TxD, RxD, GND
- **RS-485 Mode:** Half duplex, multi-drop
  - Signals: DATA+, DATA-
- Connector: Screw terminal
- Transmission speed: Up to 115.2 Kbps
- Max transmission distance:
  - RS-232: 50 feet (15.2 m)
  - RS-485: 4000 feet (1220 m)
Chapter 1 System Overview

1.3.5 Power
• Unregulated +10 to +30 VDC
• Power consumption: 2.0 W (Typically)

1.3.6 Mechanical
• Case: ABS and PC
• Plug-in screw terminal block: two 9-pin plug in screw terminals
  Accepts #14~22 AWG (0.6~1.6 mm2)

1.3.7 Environment
• Operating temperature: -10° to 70° C (14° to 158° F)
• Storage temperature: -25° to 85° C (-13° to 185° F)
• Humidity: 5 to 95 %, non-condensing
• Atmosphere: No corrosive gases

Note: Equipment will operate below 30% humidity. However, static electricity problems occur much more frequently. Make sure you take adequate precautions when you touch the equipment.
1.3.8 Dimensions

The following diagrams show the dimensions of the system unit and an I/O unit. All dimensions are in millimeters.

Figure 1-2 ADAM-4500 Series Controller Dimension
Chapter 1 System Overview

1.3.9 LED Status

There are four LED lights on the ADAM-4500 Series. The **PWR**, **RUN** and **COMM** LED can be controlled using ADAM-4500 Series library LED OFF and LED ON (refer to section 5.3.1). **BATT** LED is the battery status indicator. This LED will be on whenever the SRAM backup battery is low.

1.3.10 ADAM-4500 Series Controller System Architecture

![ADAM-4500 Series Controller System Architecture](image)

Figure 1-3 ADAM-4500 Series Controller System Architecture
Installation Guidelines
Chapter 2 Installation

This chapter explains how to install an ADAM-4500 Series Controller. A quick hookup scheme is provided that let you easily configure your system before implement it into your application.

2.1 System Requirements

Before you start to install the ADAM-4500 Series Controller, make sure the system requirements as below:

2.1.1 Host Computer Requirements

1. IBM PC compatible computer with 486 CPU (Pentium grade is recommended).
2. Microsoft XP/2000/NT/98/95 or higher versions.
3. DOS version 3.31 or higher.
4. Borland C 3.0 for DOS.
5. At least 32 MB RAM.
6. 20 MB of hard disk space available.
7. VGA color monitor.
8. 2x or higher speed CD-ROM.
9. Mouse or other pointing devices.
10. At least one standard RS-232 port (e.g. COM1, COM2).
11. One RS-485 card or RS-232 to RS-485 converter (e.g. ADAM-4520) for system communication.
12. Hub or Switch for Ethernet connection.
2.2 Hardware Installation

2.2.1 Jumper Settings

This section tells you how to set the jumpers to configure your ADAM-4500 Series Controller. It provides system default configuration and your options for each jumper. There are four jumpers on the CPU card:

- **JP2** is for the reset mode setting.
- **JP5** is for battery backup RAM setting.
- **JP6 & JP7** is for COM4 communication mode selection setting.

The following figure shows the location of the jumpers:

![Figure 2-1 ADAM-4500 Series Jumper Definition](image)
Chapter 2 Installation

Reset Mode Setting

Jumper JP2 on the CPU card lets you configure the reset mode:

1. **Watchdog timer reset mode**: if watchdog timer is enabled, it has to be cleared at least once every 1.6 seconds, or the system will reboot. Please refer to section 5.3.1 to see how to use function library to configure watchdog timer.
2. **NMI (Non-maskable interrupt) reset mode**: once the NMI is activated, the system will reboot.
3. **Non-reset mode**: there is no reset mode set for the system.

The default setting of watchdog timer is "watchdog timer reset mode". Jumper settings are shown below:

![JP2 Reset Mode Setting](image)

Battery Backup RAM Setting

Jumper JP5 on the CPU card lets you configure the battery backup for SRAM: Enable or Disable. The default setting of battery backup is "Enable". Jumper settings are shown below:

![JP5 Battery Backup RAM](image)

2.4 ADAM-4500 Series User's Manual
Chapter 2 Installation Guidelines

COM4 Communication Mode Selection Setting

The communication mode of COM4 is setting by the Jumper JP6 and JP7. Please refer to Figure 2-9 to set the communication mode. The default setting of COM4 is Programming port (RS-232 mode) for program download. You can also set COM4 as RS-485 mode. Jumper settings are listed below:

![Jumper Settings](image)

**RS-485 Programming Port**

Figure 2-4 Jumper of COM4 communication mode selection

2.3 System Wiring and Connections

This section provides basic information on wiring the power supply, I/O units, communication port connection and programming port connection.

2.3.1 Power Supply Wiring

Although the ADAM-4500 Series Controller is designed for using a standard industrial unregulated 24 V DC power supply, they accept any power unit that supplies within the range of +10 to +30 VDC. The power supply ripple must be limited to 200 mV peak-to-peak, and the immediate ripple voltage should be maintained between +10 and +30 VDC. Screw terminals +Vs and GND are for power supply wiring and the wires used should be sized at least 2 mm.

![Power Supply Wiring](image)

Figure 2-5 ADAM-4500 Series Controller power wiring
2.3.2 I/O modules wiring

The system uses a plug-in screw terminal block for the interface between I/O modules and field devices. The following information must be considered:

1. The terminal block accepts wires from 0.5 mm to 2.5 mm.
2. Always use a continuous length of wire. Do not combine wires to make them longer.
3. Use the shortest possible wire length.
4. Use wire trays for routing where possible.
5. Avoid running wires near high energy wiring.
6. Avoid running input wiring in close proximity to output wiring where possible.

The figures below show how to connect external signals to I/O connector of ADAM-4500 Series Controller.

2.3.1.1 ADAM-4501/4501D

![Figure 2-6 Dry contact wiring for DI channel](image)

Figure 2-6 Dry contact wiring for DI channel
Chapter 2 Installation Guidelines

Figure 2-7 Wet contact wiring for DI channel

Figure 2-8 Digital output wiring
2.3.1.2 ADAM-4502

Figure Analog Input wiring

Figure Analog Output wiring

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Chapter 2 Installation Guidelines

Figure Digital Input wiring

Figure Digital Output wiring

*ADAM-4500 Series User’s Manual 2-9*
2.3.3 System Network Connection

Network Connection for System Configuration and Download

The ADAM-4500 Series Controller has a Programming port. This port (COM4) allows you to program, configure, and troubleshoot the ADAM-4500 Series Controller from your host computer. The Programming port has an RS-232 interface and only uses TX, RX, and GND signals. The cable connection and the pin assignment are as follows:

![Diagram showing cable connection and pin assignment]

**PC COM port**  **straight through cable**  **ADAM-4500 series Prog. port**

<table>
<thead>
<tr>
<th>PC COM port</th>
<th>straight through cable</th>
<th>ADAM-4500 series Prog. port</th>
</tr>
</thead>
<tbody>
<tr>
<td>CD</td>
<td>1</td>
<td>TX</td>
</tr>
<tr>
<td>RX</td>
<td>2</td>
<td>RX</td>
</tr>
<tr>
<td>TX</td>
<td>3</td>
<td>GND</td>
</tr>
<tr>
<td>DTR</td>
<td>4</td>
<td></td>
</tr>
<tr>
<td>GND</td>
<td>5</td>
<td></td>
</tr>
<tr>
<td>DSR</td>
<td>6</td>
<td></td>
</tr>
<tr>
<td>RTS</td>
<td>7</td>
<td></td>
</tr>
<tr>
<td>CTS</td>
<td>8</td>
<td></td>
</tr>
<tr>
<td>RI</td>
<td>9</td>
<td></td>
</tr>
</tbody>
</table>

*Figure 2-9 System Configuration Wiring*
Chapter 2 Installation Guidelines

Note: We also provide a friendly cable for Programming port wiring. Please refer following pictures to wire the Programming port.

Figure 2-10 Cable Configuration Wiring
RS-232 Network Connection for System Monitoring and Integration

Since the connection for an RS-232 interface is not standardized, different devices implement the RS-232 connection in different ways.

If you are having problems with a serial device, be sure to check the pin assignments for the connector. We provide one cable to transfer RJ-48 (COM1 connector on ADAM-4500 Series Controller) to DB9.

The following figure shows the pin assignments of the DB9 connector for the ADAM-4500 Series Controller COM1 RS-232 port.

![Figure 2-11 Pin Assignment of COM1](image)

RS-485 Network Connection for System Monitoring and Integration

The ADAM-4500 Series Controller provides RS-485 interfaces for multi-drop network integration. The COM2 & COM3 are dedicated RS-485 interface. The COM4 is an RS-232/485 selectable COM port. They are able to support the Modbus/RTU master and slave functions.
Chapter 2 Installation Guidelines

Ethernet Network Connection

The ADAM-4500 Series Controller provides Ethernet interface (RJ-45 type) for network integration. Usually, you will need to prepare an Ethernet switch like as ADAM-6520 or hub for connecting to other network devices as following figure.

Figure 2-12 Ethernet Connection
2.4 Software Installation

ADAM-4500 Series Controller comes with a Utility CD, containing ADAM Product Series Utilities as system configuration tool. While you insert the CD into the CD drive (e.g. D:) of the host PC, the Utility software setup menu will start up automatically. Click the ADAM-4500 Series icon to execute the setup program, and there will be a Utility executive program installed in your host PC. See Chapter 3 I/O Configuration and Program Download for the detail operation.
Program Download
Chapter 3 Program Download

This chapter explains how to use the ADAM-4500 Series Utility to configure and download application programs.

3.1 System Hardware Configuration

Before the system configuration, you will need to setup the environment as mentioned in Chapter 2.1: System Requirements.

3.2 Install Utility Software on Host PC

ADAM-4500 Series Controller comes with a Utility CD, containing ADAM Product Series Utilities as system configuration tools.

1. Insert the ADAM Utility CD into the CD drive of the host PC, and the Utility software setup menu will start automatically. Click the "Install Utility" button to install ADAM Series Utility.
Chapter 3 Program Download

2. Click on the “ADAM-4500 Series Utility” to setup ADAM-4500 Series Utility.

3. There will be dialog window showing, and click the ‘Next” button.
4. Choose the dictionary path for installing ADAM-4500 Series Utility, and then click the “Next” button.

5. Set name for Program Folder and click the “Next” button.
Chapter 3 Program Download

6. Click the “Finish” button to complete the installation.

7. After the ADAM-4500 Series Utility has been installed, you will find three directories under “C:\Program Files\Advantech\ADAM-4500 Series Utility” directory as following:

```
ADAM-4500 Series Utility
  - Config (Configuration tool SIM(4501EXE)
  - Program (ADAM-4500 series utility)
  - Source (Image, function libraries and examples)
    - Drive_D (Drive D files for ADAM-4501)
      - Default_files (Needed by ADAM-4501)
      - Extension_files (Option files for ADAM-4501)
    - Example (Example programs)
      - Basic_Function (Basic function examples)
      - DemoModbus (Simple examples of Modbus/RTU and Modbus/TCP)
      - httpEx (Examples of HTTP server and CGI function)
      - Mail (Example of sending mail function)
      - Modbus/RTU (Modbus RTU examples)
      - Modbus/TCP (Modbus TCP examples)
      - TCP (Examples of TCP and UDP connections)
      - NC (All related header files)
    - Library (Function Libraries)
      - 4501_Lib (Basic function libraries)
      - http_Lib (HTTP function libraries)
      - ModRTU_Lib (Modbus RTU libraries)
      - ModTCP_Lib (Modbus TCP libraries)
      - Sockets_Lib (Socket libraries)
```
Chapter 3 Program Download

3.3 ADAM-4500 Series Utility Overview

1. Put switch into Initial mode and then reboot. (Initial mode is for configuration and download program into ADAM-4501 controller. Always set Initial mode when downloading program. Normal mode will automatically run the downloaded program in the autorun.bat file when ADAM-4500 Series Controller boots up. Refer to section 3.6 for more detail)

2. Execute Adam4500.exe under C:\Program Files\Advantech\ADAM-4500 Series Utility\Program. Select the COM Port on your PC which you use to connect to ADAM-4500 Series Controller.
Chapter 3 Program Download

3. Click the “Refresh Folder” button to display the files and directories on the drive D of ADAM-4500 Series Controller.

4. Click the “Config ADAM” button to test digital input/output on ADAM-4500 Series Controller.
Chapter 3 Program Download

5. Check if there is enough space for download this application to disk on ADAM-4500 Series Controller (Refer to the status bar). If the space is greater than 40KB, click the “Yes” button to continue.

6. Built-in example will be downloaded into the controller. You can use this example to test the functionality of DIO on ADAM-4501/4501D.
Chapter 3 Program Download

7. Click the “Launch Terminal” button for launching terminal emulation function. You can type DOS command in the termination window to communicate with ADAM-4500 Series Controller.

8. Click the “Adam-4500 Configuration” button for configuring network (such as IP address, Gateway and DNS), FTP/HTTP server settings and performing system initialization function. (Refer to section 3.4 and 3.5 for more detail)
9. Click the “Advantech Image Worker” button for backup drive D as image file or restore image file to drive D. (Refer to section 3.7 and 3.8 for more detail)

10. Click the “Download” button for downloading programs or files from host PC (on the left window) to ADAM-4500 Series Controller (on the right window).
3.4 Initialize the drive D: to default settings.

Following steps will show you how to initialize the drive D to default settings for ADAM-4500 Series Controller. The drive D of ADAM-4500 Series Controller will return to initial files and settings after this function is performed.

1. Put switch into Initial mode and then reboot.

2. Click the “Adam-4500 Configuration” button.
3. Select “HTTP FTP Server” and click the “Go” button. (This means both HTTP and FTP server will be initialized)

4. There will be window showing “Warning”, click “Yes” to initialize drive D. Please note that drive D will be formatted and all the files on drive D will be lost. If you would like to backup the drive contents, please refer to section 3.7.
5. You will find the initialization process is performing.

6. Click the “OK” button to finish the initialization process.
7. The directory of drive D will be refreshed as following picture.

8. The FTP and HTTP Server file is under “WEBROOT” directory.
3.5 Configure IP address and ftp/http user/password settings.

Following steps will show you how to configure IP address and users/password of FTP server and HTTP server for ADAM-4500 Series Controller. Please note the default IP address is “10.0.0.1”.

1. Put switch into Initial mode and then reboot.

2. Click the “Adam-4500 Configuration” button.
3. Select “Static IP” and fill in the IP address and Gateway IP. Select “Obtain DNS address automatically”. Click the “Update” button to perform the configuration.

**Note:** Above settings is only an example. You have to configure the network settings according to your network environment.

4. Click the “OK” button to finish the network configuration.
5. Fill in the user name, password and access right for FTP server and HTTP server. Click the “Update” button to perform the configuration.

**Note:** This utility can only let you configure one user for FTP server and one user for HTTP server. If you would like to configure multi-users for FTP server and HTTP server, please refer to chapter 4.

6. Click the “OK” button to finish the configuration.
3.6 Download and run the application program automatically after boot up

ADAM-4500 series can automatically run program after boot up by including the program in the autorun.bat file. Following steps will demonstrate how to run dhcpstat.exe automatically after boot up.

1. Put switch into Initial mode and then reboot.

2. Download the program dhcpstat.exe (under C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Drive_D\Extension_files) onto ADAM-4500 Series Controller by click the “Download” button.
Chapter 3 Program Download

3. Find the autorun.bat file under C:\Program
Files\Advantech\ADAM-4500 Series Utility\Source\Drive_D\Default_files on the left window (on the Host PC). Right click the autorun.bat and choose "Edit".

4. Add "D:\DHCPSTAT.EXE" in the autorun.bat file. After finishing editing, save the file and close the windows.
Chapter 3 Program Download

5. Update modified autorun.bat file onto ADAM-4500 Series Controller by choose the autorun.bat file in the left window and click the “Download” button.

6. Click the “Launch Terminal” button for launching terminal emulation function.
Chapter 3 Program Download

7. Put switch into **Normal mode** and then reboot. (In **Initial mode**, program listed in autorun.bat will not automatically run after boot up. It will automatically run after boot up only in **Normal mode**).

8. Reboot the ADAM-4500 Series Controller and check the terminal window to see if dhcpstat.exe has been executed correctly.
**Note:** There is another easier way to set program run automatically after boot up. You don’t need to modify the `autorun.bat` on the host PC and download to ADAM-4500 Series Controller.

In this example, put the switch into **Initial Mode**. Download the program `dhcpstat.exe` onto ADAM-4500 Series Controller (as shown in step 2 of the previous method).

Then right click the program `dhcpstat.exe` on the right window and choose “Set to AutoRun>>Adam-4500”. It will modify the `autorun.bat` (this has the same effect as step 3~5 of the previous method).

After that, click the “Launch Terminal” button (as shown by steps 6 of previous method). Put the switch into **Normal mode** and then reboot. Now you should see the terminal window the same as steps 8 of previous method.

---

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Chapter 3 Program Download

3.7 Backup drive D as image file.

Following steps demonstrate how to backup drive D as image file.

1. Put switch into Initial mode and then reboot.

2. Click the “Refresh” button. You can see latest files in drive D of ADAM 4500 Series Controller by the right window.
3. Click the “Advantech Image Worker” button to perform the backup function.

4. Click the “Backup Image” button.
Chapter 3 Program Download

5. There will be a warning dialog window showing. Check if there is 10KB free space on drive D of ADAM-4500 Series Controller by the status bar at the bottom of the right window. If the size is greater than 10KB, click the “Yes” button to continue.

6. Select where you want to save the image file and type the image file name. Then click the “Save” button.
7. Backup function will start to process.

8. Click the “OK” button to finish the backup process.
Chapter 3 Program Download

3.8 Restore the drive D from image file.

Following steps will demonstrate how to restore image file to drive D. In this example, we will use the image file produced in section 3.7.

1. Put switch into **Initial mode** and then reboot.

2. Click the “Advantech Image Worker” button to perform the restore function.
3. Click the “Restore Image” button.

4. There will be a warning dialog window showing. Make sure all files on drive D can be deleted. Also make sure there is 10KB free space on drive D of ADAM-4500 Series Controller by the status bar at the bottom of the right window. If everything is okay, click the “Yes” button.
5. Select the image file you want to reload. (Here we use the image file created in 3.7) Click the “Open” button.

6. Restore function will start to process.
7. Click the “OK” button to finish the restore process. Reboot the ADAM-4500 Series Controller.

8. Click the “Refresh” button. Check the drive D has been restored from the backup image file.
Guidelines for Network Functions
Chapter 4 Guidelines for Network Functions

The network features of ADAM-4500 Series Controller are very rich. In order to shorten the learning time about versatile network features, the network functions will be present by step-by-step demonstration in this chapter. The detail information of related functions, utilities and applications are shown on later chapters. The sample programs can also be found after ADAM-4500 Series Controller utility on ADAM CD is installed.

Before you start to test the network functions, you have to configure two files as following.

SOCKET.CFG: Text file contains related configuration command.
SOCKET.UPW: Text file contains user name and password.

SOCKETS Configuration Files: SOCKET.CFG, HOSTS

SOCKETS use two files in the D:\CFG directory (default) or any other directory specified by the SOCKETS environment variable. These files are SOCKET.CFG, the default start-up file, and HOSTS, the host names file. If not found, SOCKETS uses the default SOCKET.CFG in the D:\CFG directory.

SOCKET.CFG is a text file containing configuration commands. Empty lines and lines starting with # are ignored. Commands are used to specify protocol parameters like the IP address of the stack, interface parameters like Packet Driver or Asynchronous Serial lines, routes and various other parameters. Here is a simple example:

IP address demo
   Set the IP address of this host to 192.6.1.1.

Interface pdr if0 dix 1500 5
   Use Packet Driver, naming the interface ‘if0’, MTU=1500, Receive buffers = 5

Route add default if0 router
   Route all traffic to unknown destinations via ‘if0’ using ‘router’ as a gateway

TCP mss 1460
   TCP Maximum Segment Size = 1460.
TCP window 2920
TCP Maximum window = 2920.

Start prntserv
Start printer server on PRN using default port of 10.

HOSTS is an optional file containing mappings of IP addresses in dotted decimal notation to names.

Sample HOSTS file:

192.6.1.1 demo
192.6.1.2 router
192.6.1.3 server

SOCKET.CFG Samples

The following configuration file contains the minimum possible commands for a valid configuration file: just one. This is to specify that the interface should use a Packet Driver, the interrupt vector, which must be searched for. It should use DIX encapsulation, have an MTU of 1500 and have a maximum of 5 receive buffers. Since no IP address is specified, BOOTP will be used and the required operating parameters will be retrieved from a BOOTP server, which must be available on the network.

SOCKET.CFG: 
interface pdr if0 dix 1500 5

The following is a more typical example specifying a static IP address, a Packet Driver interface, a default route, the TCP MSS and WINDOW.

SOCKET.CFG: 
# Sample configuration file
ip address 192.6.1.1
interface pdr if0 dix 1500 5
route add default if0 192.6.1.2
tcp mss 1460
tcp window 2920
Format of "SOCKET.UPW"

This is the same file used for the HTTP and FTP server’s *(FTPD.EXE)* permissions. This file consists of lines where each line contains a user’s information. A line starting with a # is considered a comment and is ignored. Each line consists of four fields:

<Username> <Password> <Working Directory> <Permissions> [# comment]

- **Username**: The name of this user. If it is *, it will be used when the client does not specify a username.

- **Password**: This user’s password. If it is *, no password is required.

- **Working Directory**: The user will only have access to this directory and its subdirectories. If it is ‘/’, this user has access to the whole system. HTTP_DIR can be referred to as ‘\’. If a relative path is specified, it is appended to HTTP_DIR.

- **Permissions**: When a user is granted both FTP and HTTP permissions, the FTP permissions must appear first, otherwise they will be ignored. Permission are listed below:

  FTP Rights:
  - d change directories
  - c create/delete directories
  - w write files
  - r read files

  HTTP Rights:
  - e get files
  - p post files
  - g use CGI
  - m use remote console

Fields should be separated by single spaces. If any field is missing the entry is ignored. A comment may follow the last field (permissions) of the line.
Chapter 4 Guidelines for Network Functions

Here are two example configuration files, which are used by the following demonstrations:

**SOCKET.CFG:**

```
# Packet driver settings
ip address 192.168.1.4
interface pdr if0 dix 1500 10 0x60

# The following will cause SOCKETS to display IP status
ip address

# The following lines set TCP parameters
ip ttl 64
tcp mss 1460
tcp window 2920
```

**SOCKET.UPW:**

```
su su / drwcepgm  # su can do everything on whole system.

* * \guest rg  # everyone can read (FTP) and get (HTTP)
# from %HTTP_DIR%\guest
test1 test1 \drep  # test1 can change directories and read files (FTP)
# test1 get and post files (HTTP) in %HTTP_DIR%\
ftp1 ftp1 \guest rd  # ftp1 can read files and change directories (FTP)
# in %HTTP_DIR%\guest
# ftp1 has no HTTP rights

http1 http1 / epgm  # http1 can get and post files, use CGI,
# and use remote console.
# http1 has no FTP rights

user1 user1 \user\user1 rdcw  # user1 has full FTP access rights to the
# directory %HTTP_DIR%\user\user1
# user1 has no HTTP rights
```
4.1 FTP Server

Utility: FTPD.EXE
System configuration:
- Running FTP server on ADAM-4500 Series Controller
- FTP Client program on host PC

1. Download FTPD.EXE (under \ADAM-4500 Series Utility\Source\ Drive_D\Extension_files on Host PC) onto drive D under “Webroot” directory. (Put switch into Initial mode)
2. Put switch into Normal mode and then reboot. Type “cd webroot” to enter “Webroot” directory. Type “ftpd /r” to run FTPD.EXE at resident.

3. Connect to the FTP server on Host PC. (The IP Address of Host PC and ADAM-4500 Series Controller should be in the same domain)
Chapter 4 Guidelines for Network Functions

4. Login FTP server by typing user name and related password (user names and passwords are listed in SOCKET.UPW under \ADAM-4500 Series Utility\Source \Drive_D\Default_files\Conf)

5. Check the files under "Webroot" directory are correctly.
4.2 HTTP Server

Example program: HTTPDEMO.EXE (without CGI function)
Source file: HTTPDEMO.C under \ADAM-4500 Series Utility\Source\Example\httpEx directory (refer to Page 4-14)

Utility: HTTPD.EXE

System configuration:
- Running HTTP server on ADAM-4500 Series Controller
- Using Web Browser to connect to the HTTP server on Host PC

1. Download HTTPD.EXE under \ADAM-4500 Series Utility\Source\ Drive D\extension_files onto drive D under "Webroot" directory. (Put switch into Initial mode)
2. Using HTTPDEMO.PRJ to build HTTPDEMO.EXE (under %ADAM-4500 Series Utility\Source\Example\httpEx) and download HTTPDEMO.EXE onto drive D under “Webroot” directory.
Chapter 4 Guidelines for Network Functions

3. Put switch into **Normal mode** and then reboot.
   Type “cd webroot” to enter “Webroot” directory. Type “httpd /r” to run HTTPD.EXE at resident.

4. Type “httpdemo” to run HTTPDEMO.EXE.
5. Run IE on Host PC, type URL “http://10.0.0.1/index.htm” and login in by entering user name and password.

Note: 10.0.0.1 is the default IP of ADAM-4500 Series Controller, and refers to SOCKET.CFG under \ADAM-4500 Series Utility\Source\Drive_D\Default_files\Conf to get real IP address. You can refer to SOCKET.UPW for user name and password.

6. You should be able to see ADAM-4500 Series Controller built-in I/O board ID as shown by figure below.
The extension board ID is 0x10.
Chapter 4 Guidelines for Network Functions

The following figure is the software architecture of HTTP Server function. The HTTP Server is built-in in the ADAM-4500 series Ethernet Controller. Whenever users open the IE Browser to acquire data from ADAM-4500 series controller through Internet or Intranet, it will call up the existed web pages to provide a monitor and control portal. All of the commands from the web page must be linked via a CGI program to the C control program which handle the real read/write action in I/O channels.

Basically, there are three steps in the process of Web Monitoring & Control.
1. Registration: Register a HTML name for the web page you designed
2. User login and invoke control program: After registration, users can invoke local control program by login Server
3. Local I/O activated by local control program

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Chapter 4 Guidelines for Network Functions

HTTPDEMO.C

#include <stdio.h>
#include <stdlib.h>
#include <string.h>
#include <process.h>
#include "4500drv.h"
#include "CGI_Lib.h"

FILE *fp;
int number = 0;
int count = 1;

void ReplaceStr(char *ptr_str1, char *ptr_str2, int len_str);

void main(void)
{
  char * homepage_name = "index.htm";
  if(!Http_Server_Reg(homepage_name))
    return;

  printf("Program exiting...");
  HttpDeRegister("index.htm");
}

int far Callback(HTTP_PARAMS far* psParams)
//implement your program/in this function
{
  static char *ptr_OO = 0;
  char *tmpStr = 0;
  static char Htm_Content[] = "HTTP/1.0 200 OK
  Content-type: text/html
  <html><META HTTP-EQUIV="Refresh" content=1>
  <b>The extension board ID is OOOOOOO</b><p>
  </html>";

  return(0);
}
number++;  
printf("Refresh %d times...\n", number);

if (!ptr_OO)  
    ptr_OO = strstr(Htm_Content, "OOO");

sprintf(tmpStr, "0x%X", Get_BoardID());
ReplaceStr(ptr_OO, tmpStr, 7);

HttpSendData(psParams->iHandle, Htm_Content, strlen(Htm_Content));
return RET_DONE;
}

void ReplaceStr(char *ptr_str1, char *ptr_str2, int len_str)  //replace string
{
    int i;
    for(i=0; i<len_str; i++)
        ptr_str1[i] = 32;

    for(i=0; i<strlen(ptr_str2); i++)
        ptr_str1[i] = ptr_str2[i];
}
<<Example 2>>
Example program: ADAM.EXE (with CGI function)
Source file: ADAM.C and WEBADAM.htm under ADAM-4500 Series Utility\Source \Example\httpEx directory (refer to Page 4-21)

Utility: HTTPD.EXE

System configuration:
- Running HTTP server on ADAM-4500 Series Controller
- Using Web Browser to connect to the HTTP server on Host PC

1. Download HTTPD.EXE (under \ADAM-4500 Series Utility\Source\ Drive_D\Extension_files) onto drive D under "Webroot" directory. (Put switch into Initial mode)
2. Using ADAM.PRJ to Build ADAM.EXE (under ADAM-4500 Series Utility\Source\Example\httpEx) and download ADAM.EXE onto drive D under “Webroot” directory.

3. Download WebAdam.HTM onto drive D under “Webroot” directory.
4. Put switch into Normal mode and then reboot. Type “cd webroot” to enter “Webroot” directory. Type “httpd /r” to run HTTPD.EXE at resident.

5. Type “adam” to run ADAM.EXE.
Chapter 4 Guidelines for Network Functions

6. Run IE on Host PC, type the URL as “http://10.0.0.1/web adam.htm” (Note: 10.0.0.1 is the default IP of ADAM-4500 Series Controller, and refer to SOCKET.CFG under \ADAM-4500 Series Utility\Source\ Drive_D\Default_files\Conf to get the real IP address. You can refer to SOCKET.UPW for user name and password)

7. You can set the status for ADAM-4500 Series Controller built-in I/O board (EB50) by IE and then click the “Submit” button.
8. Then you can see if the EB50 status is correctly updated in ADAM-4500 Series Controller Utility.
#include <stdio.h>
#include <io.h>
#include <process.h>
#include <stdlib.h>
#include <string.h>
#include "4500drv.h"
#include "CGI_Lib.h"

extern unsigned _stklen = 3000;
extern unsigned _heaplen = 2000;

int far Callback(HTTP_PARAMS far* psParams);
int returnVal(char *ptr_name, char *pir_end);
int count = 1;

void main(void)
{
    char * homepage_name = "Adam.htm";
    if(!Http_Server_Reg(homepage_name))
        return;

    printf("Program exiting'n");
    HttpDeRegister("Adam.htm");
}

int far Callback(HTTP_PARAMS far* psParams)
//implement your program in this function
{
    char buf[200], *p, *ptr_val, *ppass;
    int iQueryLen;
    char Re_Htm_Content[400];
    char *pir_Re = Re_Htm_Content;
    int numberbytes;
    int DoVal, DIVal;

    *buf = 0;
Chapter 4 Guidelines for Network Functions

```c
iQueryLen = _fstrlen(psParams->szQuery);
if (iQueryLen)
    _fmemcpy (buf,psParams->szQuery, iQueryLen);

numberbytes = HttpGetData(psParams->iHandle, buf + iQueryLen, 200 - iQueryLen);

if (numberbytes < 0)
{
    if (numberbytes == (-WOULDBLK))
        return RET_OK;
    else
        printf("wrong input value\n");
}

iQueryLen += numberbytes;

ptr_Re += sprintf(ptr_Re, "HTTP/1.0 200 OK\r\n\r\n<html><h1>");
if (strncmp(buf,"DOValues=", 9) == 0) {
    ptr_val = buf + 9;
    if ((p = strchr(ptr_val,'&')) == NULL)
        printf("Please click Submit button.\n");

    printf("the DO val is 0x%x", returnVal(ptr_val, p));
    SetDO(EB50_ID, AllChannels, 0, returnVal(ptr_val, p));
}

ptr_Re += sprintf(ptr_Re, "</p></p><A HREF="/WebAdam.htm">Back</A.");
HttpSendData(psParams->iHandle, Re_Htm_Content, ptr_Re - Re_Htm_Content);
return RET_DONE;
}

int returnVal(char *ptr_name, char *ptr_end)
{
    int r_Val, buf_idx;
    char buf_val[10];

    memset(buf_val, 0, 10);
    for(buf_idx=0; buf_idx<10; buf_idx++)
```
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```c
{
    if(ptr_name == ptr_end)
        break;
    buf_val[buf_idx] = ptr_name[buf_idx];
}

sscanf(buf_val, "%X", &r_Val);
return r_Val;
}

WEBADAM.htm

<html>
<head>
</head>

<body>
    <h1>
    <p>Please enter I/O status in hexadecimal format and click Submit.</p>
    <form action="Adam.htm" method=post name="login1">
        <table>
            <tr>
                <td align=right><input name="DOValues" type=text size=30 maxlength=50></td>
            </tr>
            <tr>
                <td><input name="submit" type=submit value="Submit"></td>
            </tr>
        </table>
    </form>
    </h1>
</body>
</html>

4.3 Send Mail

Example program: AMAIL.EXE, MAIL.TXT
Source file: ALARMMAIL.C under ADAM-4500 Series Utility\Source \Example\mail directory
Utility: SENDMAIL.EXE, MAKEMAIL.EXE

ADAM-4500 series configuration:
1. Right click on the right window and choose “Make Directory” (Put switch into Initial mode)

2. Type “Mail” to name the directory and click on the “OK” button.
   This directory is for download related executives and files later.
3. Create “MAIL.txt” on the left window (on the host PC). Edit the content of this file. When you finish the editing, save the file on Host PC. This file is the content file which will be sent by e-mail later.

4. Download MAIL.txt onto drive D under “MAIL” directory.
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5. Download MAKEMAIL.EXE and SENDMAIL.EXE under \ADAM-4500 Series Utility\Source\Drive_D\Extension_files onto drive D under “MAIL” directory.

6. Using AMAIL.PRJ to Build AMAIL.EXE (under \ADAM-4500 Series Utility\Source\Example\mail) directory and download AMAIL.EXE onto drive D under “WEBROOT” directory.
7. Put switch into **Normal mode** and then reboot. Type "cd mail" to enter "Mail" directory. Type "amail" to run AMAIL.EXE. This executive will execute MAKEMAIL.EXE to build e-mail content. Type the DO output value to trigger the action to send e-mail.

8. The executive will execute SENDMAIL.EXE to send the e-mail content created by previous step.
Chapter 4 Guidelines for Network Functions
9. Check the mailbox and it should receive the email correctly.

**Note:** The IP address of ADAM-4500 series should be at the same domain with the IP address of mail server, which will help you to send out the email from ADAM-4500 series. If you ask another mail server whose IP address is not at the same domain, the mail server will verify the IP address of the email sending from and then stop to provide service for sending out the email for ADAM-4500 series.
Chapter 4 Guidelines for Network Functions

ALARMMAIL.C

#include <stdio.h>
#include <process.h>
#include <errno.h>
#include "4500drv.h"

int SendAlarmMail(void);
int MakeAlarmMail(void);
int count = 1;
void main(void)
{
  unsigned long div, dov;
  unsigned int tmpcnt;

  if(!MakeAlarmMail())
  {
    printf("make mail fail.");
    return;
  }

  while(1)
  {
    printf("Please input digital output values: ");
    scanf("%X", &dov);
    if(dov == 0x33)
      return;
    printf("DO value 0x%X, press any key to continue\n", dov);
    getch();
    GetDIO(EB50_ID, AllChannels, 0, &div);
    if(div == 0x000f)
      {
        if(!SendAlarmMail())
        {
          printf("send mail error.");
          return;
        }
      }
  }
}
int MakeAlarmMail(void)
{
    char * arg_To = "-t567@123.com";
    char * arg_From = "-f345@hotmail.com";
    char * arg_subject = "-s5510TCP";
    char * arg_MailContent = "-bmail.txt";
    char * arg_O_mail = "-omail.dat";

    printf("Making Mail.\n");
    if(spawnlp(P_WAIT,
        "d:\mail\makemail.exe",
        "d:\mail\makemail.exe",
        arg_To,
        arg_From,
        arg_subject,
        arg_MailContent,
        arg_O_mail,
        NULL)==-1)
    { return 0; }
}

int SendAlarmMail(void)
{
    char * arg1 = "smtp.123.com";
    char * arg2 = "mail.dat";

    printf("send Alarm mail prepare.\n");
    if(spawnlp(P_WAIT,"d:\mail\sendmail.exe","d:\mail\sendmail.exe",
        arg1,arg2,NULL)==-1)
    { return 0; }
}

return 1;

Note: Please refer to Chapter 6 Page 6-10 and 6-11 to see more detail about Mail Function.
4.4 Modbus/TCP Server

Example program: DEMOTS.EXE
Source file: DEMOTS.C under ADAM-4500 Series Utility\Source\Example\DemoModbus directory

Hardware configuration: see figure below

This example uses ADAM-4500 Series Controller as Modbus/TCP server, and a PC on the same Ethernet network is Modbus/TCP client. ADAM-4500 Series Controller writes on-board DIO value to address 40001, and Modbus/TCP client application such as OPC Server or ADAMVIEW read the value from that address. (Address 0 of share memory represents the address 40001 of
Modbus address)
Chapter 4 Guidelines for Network Functions

1. Click the “Adam-4500 Configuration” button to set IP address of ADAM-4500 Series Controller (Put switch into **Initial mode**)

2. Build `DEMOTS.EXE` from `DEMOTS.PRJ` under `\ADAM-4500 Series Utility\Source\Example\DemoModbus` directory and download `DEMOTS.EXE` onto drive D under root directory.
3. Put switch into Normal mode and then reboot. Under the root directory, run DEMOTS.EXE. This will launch Modbus/TCP server on ADAM-4500 Series Controller.

4. Launch Advantech Modbus TCP OPC Server.
5. Create New Device under Advantech Modbus TCP OPC Server. Set the correct IP address according to step 1.

6. Right click on the new device you have just created and choose "New Tag".
7. Configure the Tag Property.

8. You can see the value of address 40001 from Modbus/TCP server on ADAM-4500 Series Controller.
#include "mod.h"
#include "4500drv.h"

#define DATASIZE 250
#define sizeofShareMem 4000

int count=0;

int main(void)
{
    SOCKET Sock_4500;
    int err_code;
    unsigned int Share_Mem[sizeofShareMem];
    unsigned int tmpcnt=0;
    int tmpidx;
    unsigned long div;

    memset(Share_Mem, 0, sizeof(Share_Mem));
    if((err_code=ADAMTCP_ModServer_Create(502, 5000, 7,
        (unsigned char *)Share_Mem, sizeof(Share_Mem)))!=0)
    //first step
    {
        printf("error code is %d\n", err_code);
    }

    Timer_Init();
    tmpidx = Timer_Set(1000);
    printf("Server started, wait for connect...\n");
    while(1)
    {
        ADAMTCP_ModServer_Update();  //second step: return 0
        //NO packet, return 1 has packet
        if(tmArriveCnt[tmpidx])
        {
            Timer_Reset(tmpidx);
            disable();
            GetDIO(EB50_ID, AllChannels, 0, &div);
        }
    }
}
Chapter 4 Guidelines for Network Functions

```
Share Mem[0] = div;
//write DIO status to modbus address 40001
enable();
}

ADAMTCP_ModServer_Release();

return 0;
```
4.5 Modbus/TCP Client

Example program: **DEMOTC.EXE**
Source file: **DEMOTC.C** under \ADAM-4500 Series Utility\Source \Example\DemoModbus directory

Hardware configuration: see figure below

This example uses ADAM-4500 Series Controller as Modbus/TCP client to connect to the ADAM-6051 (support Modbus/TCP protocol and can be a Modbus/TCP server here), and read the DI value of ADAM-6051 through Modbus/TCP communication.
Chapter 4 Guidelines for Network Functions

1. Build DEMOTC.EXE from DEMOTC.PRJ under \ADAM-4500 Series Utility\Source\Example\DemoModbus directory and download DEMOTC.EXE onto drive D under root directory. (Put switch into Initial mode)

2. Put switch into Normal mode and then reboot. Run DEMOTC.EXE (remember to add IP address of ADAM-6051) to launch Modbus/TPC client on ADAM-4500 Series Controller. You can get DI value of ADAM-6051 now.
```c
#include "mod.h"

#define Server_Port 502
#define MAXDATASIZE 100

int main(int argc, char *argv[]) {
    char *ServerIP;
    SOCKET SO_4500;
    unsigned char HostData[MAXDATASIZE];
    int DataByteCount = 0;
    int tmp;
    unsigned int tmpcnt=0, tmpcnt1=0;
    int errcode;

    memset(HostData, MAXDATASIZE, 0);

    if(argc==2) {
        ServerIP = argv[1];
    } else {
        printf("Please input Server IP.
");
        return 0;
    }

    if(ADAMTCP_Connect(&SO_4500, ServerIP, Server_Port)<=0) {
        perror("ADAMTCP_Connect()
");
        ADAMTCP_Disconnect(&SO_4500);
        return 0;
    }

    printf("Starting to send..
");
    while(1) {
        //Query Adam-6051 Server
        if((errcode=ADAMTCP_ReadCoilStatus(&SO_4500, 50, 0x01, 0x01, &DataByteCount, HostData))<=0)
```

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```c
if(errcode==TCPTimeOut_Err)
    perror("Time Out\n");
else
    printf("Error: Error Code is %d\n", errcode);
ADAMTCP_Disconnect(&SO_4500);
return 0;
}
else
{
    printf("Adam-6051 Channel 0 Status: ");
    for(tmp=0; tmp<DataByteCount; tmp++)
    {
        printf("%2X", HostData[tmp] & 0x01);
    }
    printf("\n");
}
for(tmpcnt=0; tmpcnt<50000; tmpcnt++) //delay
{for(tmpcnt1=0; tmpcnt1<4; tmpcnt1++){};
}
return 1;
}```
Chapter 4 Guidelines for Network Functions

4.6 Modbus/RTU Slave

Example program: DEMORS.EXE
Source file: DEMORS.C under \ADAM-4500 Series Utility\Source \Example\DemoModbus directory
Hardware configuration: see figure below

This example uses ADAM-4500 Series Controller as Modbus/RTU slave, and a PC on the same serial network is Modbus/RTU master. ADAM-4500 Series Controller writes onboard DIO value to address 40001, and Modbus/RTU client application such as OPC Server or ADAMVIEW read the value from that address. (Address 0 of share memory represents the address 40001 of Modbus address)
Chapter 4 Guidelines for Network Functions

1. Build DEMORS.EXE from DEMORS.PRJ under ADAM-4500 Series Utility\Source \Example\DemoModbus directory and download DEMORS.EXE onto drive D under root directory. (Put switch into Initial mode)

2. Run DEMORS.EXE. ADAM-4500 Series Controller will launch Modbus/RTU master and write DIO value to address 40001.
3. Launch Advantech Modbus OPC Server.

4. Create New Device under Advantech Modbus OPC Server. (Set Address as 3 according to the configuration in DEMORS.C)
5. Right click on the new device you have just created and choose “New Tag”.

6. Configure the Tag Property.
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7. Click “Monitor” under menu “View” to see the value get from ADAM-4500 Series Controller.

8. You can see the DIO value of ADAM-4500 Series Controller.
#include <stdio.h>
#include <dos.h>
#include <time.h>
#include <conio.h>
#include "4500drv.h"
#include "RTU.h"

#define MAXDATASIZE 100
#define sizeofShareMem 10

int count;

void main()
{
    unsigned int Share_Mem[sizeofShareMem];
    char cCh;
    char LSR_State;
    unsigned int tmpcnt, tmpcnt1;
    unsigned long div;

    if(Modbus_COM_Init(COM2, Slave, (unsigned long)9600,
        NO_PARITY, DATA8, STOP1)!==0)
    {
        printf("error\n");
        return;
    }

    printf("init success!!\n");

    ADAMRTU_ModServer_Create(3, (unsigned char *)Share_Mem,
        sizeof(Share_Mem));
    //
    //    printf("err code is %d\n", Error_Code());
    //    return;
    //

    printf("server started..\n");

    while(1)
    {
        disable();
        GetDIO(EB50_ID, AllChannels, 0, &div);
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Share_Mem[0] = div;
//write DIO status to modbus address 40001
enable();

for(tmpcnt=0; tmpcnt<50000; tmpcnt++)  //delay
  {for(tmpcnt1=0; tmpcnt1<8; tmpcnt1++){}}

}
4.7 Modbus/RTU Master

Example program: DEMORC.EXE
Source file: DEMORC.C under \ADAM-4500 Series Utility\Source \Example\DemoModbus directory

Hardware configuration: see figure below

This example uses ADAM-4500 Series Controller as Modbus/RTU master to connect to the ADAM-4056S (support Modbus/RTU protocol and can be a Modbus/RTU slave here), and the DIO value of ADAM-4056S module can be controlled by ADAM-4500 Series

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Controller through Modbus/RTU communication.
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1. Build DEMORC.EXE from DEMORC.PRJ under \ADAM-4500 Series Utility\Source \Example\DemoModbus directory and download DEMORC.EXE onto drive D under root directory. (Put switch into initial mode)

2. Run DEMORC.EXE and you will find the connection is successful as following figure. You will also find the LEDs of ADAM-4056S periodically switch ON/OFF by the command from DEMORC.EXE.

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```c
#include <stdio.h>
#include <dos.h>
#include <time.h>
#include "RTU.h"

#define MAXDATASIZE 100

void main()
{
    unsigned char HostData[MAXDATASIZE];
    int cnt=0;
    unsigned int tmpcnt=0, tmpcnt1=0;

    if(Modbus_COM_Init(COM2, Master, (unsigned long)9600, NO_PARITY, DATA8, STOP1)!=0)
    {
        printf("error\n");
        return;
    }

    printf("init success!!\n");

    while(1)
    {
        cnt++;
        if(cnt%2==0)
        {
            HostData[1]=0x0f;
            HostData[0]=0xff;
        }
        else
        {
            HostData[1]=0x00;
            HostData[0]=0x00;
        }
        if(cnt==10)
        {
            cnt = 0;
        }
        //Set 4056S status
        if(!ADAMRTU_ForceMultiCoils(COM2, 0x02, 0x11, 0x0c, 0x02, HostData))
```
\{ 
    printf("err code is %d\n", Error_Code());
    printf("fail send.");
\}

else
    printf("Success!!\n");

for(tmpcnt=0; tmpcnt<50000; tmpcnt++)  //delay
    for(tmpcnt1=0; tmpcnt1<4; tmpcnt1++){}

\}
4.8 TCP Server and Client

Example program: **TSERVER.EXE** and **TCLIENT.EXE**
Source file: **TCP_SERVER.C** and **TCP_CLIENT.C** under \ADAM-4500 Series Utility\Source \Example\TCP directory

Hardware configuration: see figure below

This example uses one ADAM-4500 Series Controller as TCP client to connect to another ADAM-4500 Series Controller (as TCP server). They can exchange data between each other through TCP/IP communication.
1. Put switch of the two ADAM-4500 Series Controllers into Initial mode. Click the “Adam-4500 Configuration” button to set IP address for TCP Server (ADAM-4500 Series Controller).

2. Click the “Adam-4500 Configuration” button to set IP address for TCP Client (another ADAM-4500 Series Controller).
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3. Build TSERVER.EXE from TSERVER.PRJ under \ADAM-4500 Series Utility\Source \Example\TCP and download it onto drive D of the ADAM-4500 Series Controller which is the TCP server.

4. Build TCLIENT.EXE from TCLIENT.PRJ under \ADAM-4500 Series Utility\Source \Example\TCP directory and download it onto drive D of the ADAM-4500 Series Controller which is the TCP client.
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5. Put switch of the two ADAM-4500 Series Controllers into Normal mode and reboot the two controllers. Run TSERVER.EXE on the ADAM-4500 Series Controller which is the TCP server.

6. Run TCLIENT.EXE (add IP address of TCP server which you set in step 1 as parameter) on another ADAM-4500 Series Controller which is the TCP client. You should see the data received.
#include <stdio.h>
#include <stdlib.h>
#ifdef _MSC_VER
#include <malloc.h>
#else
#include <mem.h>
#endif
#include <string.h>
#include <conio.h>
#include <errno.h>
#include "socket.h"
#define Errno errno
#define FALSE 0
#define TRUE 1
#define Host_Port 5510
#define Max_Conn 40
#define MAXDATASIZE 100

SOCKET remoteSocket[Max_Conn];
int WaitSocketCount[Max_Conn];
int socketTotal = 0;
int timeoutRelease = FALSE;

void ReleaseClient(int idx_so);

int main(void)
{
    SOCKET Sock_4500, New_Conn;
    struct sockaddr_in Host_addr;
    struct sockaddr_in Client_addr;
    int sin_size;
    int hasConnect, hasMessage;
    int maxSocket, sidx, New_Sidx, numbytes, sidx2;
    char buf[MAXDATASIZE];
    unsigned long pulArgp;
    char *str;
    int tmpcount=1;

    if ((Sock_4500 = socket(AF_INET, SOCK_STREAM, 0)) == INVALID_SOCKET)
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```c
{  perror("socket");  exit(1); }

Host_addr.sin_family = AF_INET;
Host_addr.sin_port = htons(Host_Port);
Host_addr.sin_addr.s_addr = INADDR_ANY;
memset(&Host_addr.sin_zero, 0, 8);

if (bind(Sock_4500, (struct sockaddr *)&Host_addr, sizeof(struct sockaddr)) == SOCKET_ERROR)
  {  perror("bind");             exit(1);  }

pulArgp = 1;
if (ioctlsocket(Sock_4500, FIONBIO, &pulArgp))
  {  perror("ioctlsocket");         exit(1);  }

if (listen(Sock_4500, 5) == SOCKET_ERROR)
  {  perror("listen");             exit(1);  }

hasMessage = FALSE;
memset(WaitSocketCount, 0, sizeof(WaitSocketCount));
printf("Server started, wait for connect...
");
while(1)
  {  if (socketTotal > 0)
      hasConnect = Host_WaitForClient(Sock_4500, 0);
    else
      hasConnect = Host_WaitForClient(Sock_4500, 5);
  }
```
if(hasConnect) {
    printf("Receive client connect request...\n");
    sin_size = sizeof(struct sockaddr_in);
    if ((New_Conn = accept(Sock_4500, (struct sockaddr *)&Client_addr,
          &sin_size)) == INVALID_SOCKET) {
        perror("accept");
        continue;
    }

    if (New_Conn != INVALID_SOCKET) {
        if (socketTotal < Max_Conn) {
            remoteSocket[socketTotal] = New_Conn;
            New_Sidx = socketTotal;
            socketTotal++;
        } else {
            if (send(New_Conn, "Connetion full, you are going to be disconnected!\n", 50, 0) == SOCKET_ERROR) {
                perror("send");
                closesocket(New_Conn);
                printf("Connetion full, disconnect client!\n");
            } else {
                printf("(TCP) Invalid incoming socket!\n");
            }
        }
    }

    str = "Hello, world!\n";
    if (send(remoteSocket[New_Sidx], str, strlen(str), 0) == SOCKET_ERROR) {
        perror("send");
    }

    if(socketTotal>0) {
        for(sidx=0; sidx<socketTotal; sidx++) {
            hasMessage = Host_WaitForClient(remoteSocket[sidx], 0);
        }
    }
}
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if(hasMessage) {
    if((numbytes=recv(remoteSocket[sidx], buf, sizeof(buf), 0)) == SOCKET_ERROR) {
        ReleaseClient(sidx);
    } else {
        if(numbytes>0)
            printf("Server receive: %s", buf);
        if(tmpcount%2==0)
            str = "ACK\n"; else
            str = "ACK\n";
        if(numbytes==0) {
            ReleaseClient(sidx);
        } else if(send(remoteSocket[sidx], str, strlen(str), 0) == SOCKET_ERROR) {
            ReleaseClient(sidx);
        }
        memset(buf, 0, sizeof(buf));
        tmpcount++;
        if(tmpcount>100) tmpcount = 1;
        WaitSocketCount[sidx] = 0;
    }
    else
        WaitSocketCount[sidx]++;
        if(WaitSocketCount[sidx]>10000) {
            timeoutRelease = TRUE;
        }
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```c
ReleaseClient(sidx);

return 0;

int Host_WaitForClient(int WaitSocket, int i_iWaitMilliSec)
{
    FD_ZERO(&FdSet);
    struct timeval waitTime;
    FD_SET(WaitSocket, &FdSet);
    waitTime.tv_sec = i_iWaitMilliSec / 1000;
    waitTime.tv_usec = (i_iWaitMilliSec % 1000)*1000L;
    if (select(0, &FdSet, NULL, NULL, &waitTime) > 0)
        return TRUE;
    return FALSE;
}

void ReleaseClient(int idx_so)
{
    int sidx, sidx2;
    sidx = idx_so;
    if(timeoutRelease)
    {
        if (send(remoteSocket[sidx], "Connection timeout, you are going to be disconnected!
", 53, 0) == -1)
            perror("send");
    }
    if(remoteSocket[sidx]!=INVALID_SOCKET)
    {
        if(closesocket(remoteSocket[sidx])!=0)
            printf("Release client resource fail!");
    }
```
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```c
for(sidx2 = sidx; sidx2 <= socketTotal-1; sidx2++)
{
    if(sidx2 < socketTotal-1)
    {
        WaitSocketCount[sidx2] = WaitSocketCount[sidx2+1];
        remoteSocket[sidx2] = remoteSocket[sidx2+1];
    }
    else if(sidx2 == socketTotal-1)
    {
        WaitSocketCount[sidx2] = 0;
        remoteSocket[sidx2] = NULL;
    }
}

socketTotal--;

if(timeoutRelease)
    printf("Connection timeout, disconnect client %d\n", sidx);
else
    printf("Socket error, disconnect client %d\n", sidx);

if(socketTotal == 0)
    printf("Wait for client connect...\n");

timeoutRelease = FALSE;
```
#include <stdio.h>
#include <stdlib.h>
#ifdef _MSC_VER
#include <malloc.h>
#else
#include <malloc.h>
#endif
#include <string.h>
#include <conio.h>
#include <errno.h>
#include "socket.h"
#define Errno errno
#define Server_Port 5510
#define MAXDATASIZE 100

int main(int argc, char *argv[])
{
    SOCKET SO_4500;
    int numbytes=0;
    char buf[MAXDATASIZE];
    struct hostent *he;
    struct sockaddr_in Server_addr;
    char *str1, *str2, *str;
    int tmpcount=1;

    str1 = "TCP\n";
    str2 = "Client\n";

    if (argc != 2)
    {
        fprintf(stderr, "usage: server hostname\n");
        exit(1);
    }

    if ((he=gethostbyname(argv[1])) == NULL)
    {
        perror("gethostbyname");
        exit(1);
    }

    if ((he=gethostbyname(argv[1])) == NULL) {
        perror("gethostbyname");
        exit(1);
    }
if ((SO_4500 = socket(AF_INET, SOCK_STREAM, IPPROTO_TCP)) == INVALID_SOCKET)
{
    perror("socket");
    exit(1);
}

Server_addr.sin_family = AF_INET;
Server_addr.sin_port = htons(Server_Port);
Server_addr.sin_addr = *((struct in_addr *)he->h_addr);
memset(&(Server_addr.sin_zero), 0, 8);

if (connect(SO_4500, (struct sockaddr *)&Server_addr, sizeof(struct sockaddr)) == SOCKET_ERROR)
{
    perror("connect");
    exit(1);
}

while(1)
{
    if ((numbytes=recv(SO_4500, buf, MAXDATASIZE-1, 0)) == SOCKET_ERROR)
    {
        perror("recv");
        exit(1);
    }
    if(numbytes>0)
    {
        printf("Received: %s",buf);

        memset(buf, 0, sizeof(buf));
        if(tmpcount%2==0)
            str = str1;
        else
            str = str2;

        sleep(1);
        if (send(SO_4500, str, strlen(str), 0) == SOCKET_ERROR)
        {
        }
perror("send");
exit(1);
}
tmpcount++;
if(tmpcount>100)
tmpcount=1;
} else {

closesocket(SO_4500);
break;
}
return 0;
}
4.9 UDP Connection

Example program: USERVER.EXE and UCLIENT.EXE
Source file: UDP_SERVER.C and UDP_CLIENT.C under \ADAM-4500 Series Utility\Source\Example\TCP directory

Hardware configuration: see figure below

This example uses one ADAM-4500 Series Controller as UDP client to connect to another ADAM-4500 Series Controller (as UDP server). They can exchange data between each other through UDP communication.
1. Put switch of the two ADAM-4500 Series Controllers into Initial mode. Click the “Adam-4500 Configuration” button to set IP address for Server (ADAM-4500 Series Controller)

2. Click the “Adam-4500 Configuration” button to set IP address for Client (another ADAM-4500 Series Controller)
3. Build `USERVER.EXE` from `USERVER.PRJ` under `\ADAM-4500\Series Utility\Source\Example\TCP` and download it onto drive D of the ADAM-4500 Series Controller which is the UDP server.

4. Build `UCLIENT.EXE` from `UCLIENT.PRJ` under `\ADAM-4500\Series Utility\Source\Example\TCP` and download it onto drive D of the ADAM-4500 Series Controller which is the UDP client.
5. Put switch of the two ADAM-4500 Series Controllers into **Normal mode** and reboot the two controllers. Run USERVER.EXE on the ADAM-4500 Series Controller which is the UDP server.

6. Run UCLIENT.EXE (add IP address of TCP server which you set in step 1 as parameter) on another ADAM-4500 Series Controller which is the UDP client. You can see the data sent from server.
#include <stdio.h>
#include <stdlib.h>
#ifdef _MSC_VER
#include <malloc.h>
#else
#include <mem.h>
#endif
#include <string.h>
#include <conio.h>
#include <errno.h>
#include "socket.h"

#define Errno errno
#define FALSE 0
#define TRUE 1
#define Host_Port 5510
#define MAXBUFLEN 100

int main(void)
{
    SOCKET Host_Sock;
    struct sockaddr_in Host_addr;
    struct sockaddr_in Client_addr;
    int hasMessage = FALSE;
    unsigned long pulArgp;
    char buf[MAXBUFLEN];
    int addr_len, numbytes;
    char* ackmsg = "ACK";

    if ((Host_Sock = socket(PF_INET, SOCK_DGRAM, IPPROTO_UDP)) == INVALID_SOCKET)
    {
        perror("socket");
        exit(1);
    }

    Host_addr.sin_family = AF_INET;
    Host_addr.sin_port = htons(Host_Port);
    Host_addr.sin_addr.s_addr = INADDR_ANY;
    memset(&(Host_addr.sin_zero), 0, 8);
if (bind(Host_Sock, (struct sockaddr *)&Host_addr, sizeof(struct sockaddr)) == SOCKET_ERROR)
{
    perror("bind");
    exit(1);
}

pulArgp = 1;
if (ioctlsocket(Host_Sock, FIONBIO, &pulArgp))
{
    perror("ioctlsocket");
    exit(1);
}

printf("wait for client send message...\n");

while(1)
{
    hasMessage = Host_WaitForMessage(Host_Sock, 0);

    if(hasMessage)
    {
        addr_len = sizeof(struct sockaddr);
        if ((numbytes = recvfrom( Host_Sock, buf, sizeof(buf), 0,
                                   (struct sockaddr *)&Client_addr, &addr_len)) ==
            SOCKET_ERROR)
        {
            perror("recvfrom");
            if (errno == EWOULDBLOCK)
                printf("EWOULDBLOCK");
            break;
        }
        buf[numbytes] = 0;
        printf("got packet \"%s\" from %s\n", buf,
               inet_ntoa(Client_addr.sin_addr));

        if ((numbytes = sendto(Host_Sock, ackmsg, strlen(ackmsg), 0,
                                (struct sockaddr *)&Client_addr, sizeof(struct sockaddr))) ==
            SOCKET_ERROR)


```c
{ 
perror("sendto");
break;
}
}
closesocket(Host_Sock);
return 0;
}

int Host_WaitForMessage(int serverSocket, int i_iWaitMilliSec)
{
    fd_set FdSet;
    struct timeval waitTime;

    FD_ZERO(&FdSet);
    FD_SET(serverSocket, &FdSet);
    waitTime.tv_sec = i_iWaitMilliSec / 1000;
    waitTime.tv_usec = (i_iWaitMilliSec % 1000)*1000L;

    if (select(0, &FdSet, NULL, NULL, &waitTime) > 0)
        return TRUE;
    return FALSE;
}
```
#include <stdio.h>
#include <stdlib.h>
#ifndef _MSC_VER
#include <malloc.h>
#else
#include <malloc.h>
#endif
#include <string.h>
#include <conio.h>
#include <errno.h>
#include "socket.h"
#define Errno errno
#define BufferSize  100
#define Host_Port 5510

int main(int argc, char * argv[])
{
    SOCKET SO_4500;
    struct sockaddr_in Server_addr;
    struct sockaddr_in From_Addr;
    struct hostent * he;
    char buf[BufferSize];
    int numbytes;
    unsigned int From_Size;
    char* msg = "UDP Client Conneted!";

    if (argc != 2)
    {
        fprintf(stderr,"usage: uclient xxx.xxx.xxx.xxx\n");
        exit(1);
    }

    if ((he=gethostbyname(argv[1])) == NULL)
    {
        perror("gethostbyname");
        exit(1);
    }

    if ((SO_4500 = socket(AF_INET, SOCK_DGRAM, IPPROTO_UDP)) == INVALID_SOCKET)
    {
        perror("socket");
    }
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```c
exit(1);
}

Server_addr.sin_family = AF_INET;
Server_addr.sin_port = htons(Host_Port);
Server_addr.sin_addr = *((struct in_addr *)he->h_addr);
memset(&(Server_addr.sin_zero), 0, 8);

if ((numbytes=sendto(SO_4500, msg, strlen(msg), 0, (struct sockaddr *)&Server_addr, sizeof(struct sockaddr))) == SOCKET_ERROR)
{
    perror("sendto");
    exit(1);
}

printf("sent %d bytes to %s\n", numbytes,
inet_ntoa(Server_addr.sin_addr));

From_Size = sizeof(From_Addr);
if ((numbytes = recvfrom(SO_4500, buf, sizeof(buf), 0, (struct sockaddr *)&From_Addr, &From_Size)) == -1)
{
    perror("recvfrom");
    exit(1);
}

buf[numbytes] = 0;
printf("got Ack packet \"%s\" from %s\n", buf,
inet_ntoa(From_Addr.sin_addr));

closesocket(SO_4500);

return 0;
}
4.10 FTP Client

1. Put switch into Initial mode. Download FTP.EXE under \ADAM-4500 Series Utility\Source\Drive_D\Extension_files\WebRoot onto drive D under "Webroot" directory.

2. Put switch into Normal mode and reboot. Type “cd webroot” to enter "Webroot" directory. Run FTP.EXE (add the FTP address of the FTP server you want to connect).
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3. Login FTP server by typing your username and password. Then you can start to enter FTP command to use the FTP server.
5.1 Introduction

User-designed ADAM-4500 Series Controller application programs make use of ADAM-4500 Series library functions. To make the most efficient use of ADAM-4500 Series Controller's memory space, the ADAM-4500 Series function library has been separated into 10 smaller libraries. Therefore, a user can link only those libraries needed to run his application, and only those libraries will be included in the compiled executable. The smaller the linked libraries, the smaller the compiled executable will be.

5.1.1 Programming detail about the ADAM-4500 Series Controller

The operating system of ADAM-4500 Series Controller is ROM-DOS, which is a MS-DOS equivalent system. It allows users to run application programs written in assembly language as well as high-level languages such as C or C++. Certainly, there will be some limitations when running application programs in the ADAM-4500 Series Controller. In order to build successful applications, please keep the following limitations and concerns in mind.

5.1.2 Mini BIOS functions

The ADAM-4500 Series Controller provides four serial communication ports including programming port for connecting peripherals, so the mini BIOS of ADAM-4500 Series Controller only provides 10 function calls. Since the user's program cannot use other BIOS function calls, the ADAM-4500 Series Controller may not work as intended. Additionally, certain language compilers such as QBASIC directly call BIOS functions that are not executable in ADAM-4500 Series Controller. The ADAM-4500 Series Controller mini BIOS function calls are listed in the following table.
Table 5-1: ADAM-4500 Series Controller mini BIOS function calls

5.1.3 Converting program codes

The ADAM-4500 Series Controller has an 80188 CPU. Therefore, programs downloaded into its flash ROM must be converted into 80186 or 80188 compatible codes firstly, and the floating point operation must be set to Emulation Mode. For example, if you develop the application program in Borland C, you will compile the program as following picture.
5.1.4 Libraries Sized for Different Memory Modes

The ADAM-4500 Series function libraries support four memory models: SMALL, MEDIUM, COMPACT and LARGE. You can use library files sized according to your memory model. For example, if you use small model you can link UTILITYS.LIB and LIOS.LIB to implement system and low speed I/O module access functions. On the other hand, if you use large model, you can link UTILITYL.LIB and LIOL.LIB.
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5.1.5 Limitations

Certain critical files are always kept in flash ROM, such as operating system, BIOS, and monitoring files. The ADAM-4500 Series Controller provides an additional 1MB flash disk as drive D. There is up to 960KB free space for user's application program. As some additional system files and network utilities for ADAM-4500 Series Controller is distributed on drive D, the free space for user's application program should be less than 960KB. Besides, there are 256KB flash memory and up to 384KB battery SRAM for user's applications which can be accessed by function library.

Figure 5-3: Select “Code generation”

Figure 5-4: Select “Small” Model while using *S.LIB

Warning: The free space of flash disk is not suitable for frequently creating and deleting files such as periodic data logging application because the DOS FAT file system is probably destroyed by critical operations while the disk is almost full. The better way is to take the operations on battery backup SRAM.

5.1.6 Programming the watchdog timer

The ADAM-4500 Series Controller is equipped with a watchdog timer function that resets the CPU or generates an interrupt if processing comes to a standstill for any reason. This feature increases system reliability in industrial standalone and unmanned environments.

If you decide to use the watchdog timer, you must write a function call to enable it. When the watchdog timer is enabled, it must be cleared by the application program at intervals of less than 1.6 seconds. If it is not cleared at the required time intervals, it will activate and reset the CPU, or generate a NMI (Non-Maskable Interrupt). You can use a function call in your application program to clear the watchdog timer. At the end of your program, you still need a function call to disable the watchdog timer.
5.2 Category of Function Libraries

ADAM-4500 Series Controller has 10 categories of function libraries as following:

- Category A. System Functions (UTILITY*.LIB)
- Category B. I/O Module Functions (HIO*.LIB)
- Category C. Communication Functions (A4_COMM*.LIB)
- Category D. MODBUS/RTU Functions (RTU*.LIB)
- Category E. MODBUS/TCP Functions (MBTCP*.LIB)
- Category F. Socket Functions (SOCKET*.LIB)
- Category G. HTTP Functions (CGI_LIB*.LIB)

Note 1: These function libraries support Borland C 3.0 for DOS only.
Note 2: Please include all necessary ADAM-4500 Series function libraries in your project file.

5.2.1 Category A: System Functions (UTILITY*.LIB)

adv_printf()  
ADAMdelay  
Get_BoardID  
Get_NodeID  
GetRTCtime  
SetRTCtime  
LED_init  
LED_OFF  
LED_ON  
EraseSector  
ProgramByte  
ProgramSector  
read_mem  
Get_SysMem  
Set_SysMem  
Get_NVRAM_Size  
Set_NVRAM_Size  
write_backup_ram  
read_backup_ram  
Timer_Init  
Timer_Reset  
Timer_Set  
Release_All  
tmArriveCnt
WDT_clear
WDT_disable
WDT_enable
display_inti()
display_digit()
BatteryStatus()
Ver()

5.2.2 Category B: I/O Module Functions (HIO*.LIB)

InitDIFilter()
GetDIO()
SetDIO()
Ver_HIOLib()
GetAI()
SetAO()
SetAIRange()
SetAORange()
SetAISpeed()

5.2.3 Category C: Communication Functions: (A4_COMM*.LIB)

SIO_Open()
SIO_Close()
SIO_SetState()
SIO_RecvBytes()
SIO_SendBytes()
SIO_GetAvaiRecvBytes()
SIO_GetAvaiSendBuf()
SIO_PurgeBuf()
SIO_MakeCheckSum()
SIO_MakeCRC16()
SIO_Carrier()
SIO_ClearBreak()
SIO_SetBreak()
SIO_GetLineStatus()
SIO_SetLineParams()
SIO_GetModemStatus()
SIO_LowerRaise_RTS_DTR()
SIO_ModemInitial()
SIO_ModemAutoanswer()
SIO_ModemCommand()
SIO_ModemCommand_State()
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SIO_ModemDial()
SIO_ModemHandup()
Ver_COMLib()
5.2.4 Category D: MODBUS/RTU Functions (RTU*.LIB)

- Modbus_COM_Init()
- Modbus_COM_Release()
- Error_Code()
- ADAMRTU_ForceMultiCoils()
- ADAMRTU_ForceSingleCoil()
- ADAMRTU_PresetMultiRegs()
- ADAMRTU_PresetSingleReg()
- ADAMRTU_ReadCoilStatus()
- ADAMRTU_ReadHoldingRegs()
- ADAMRTU_ReadInputRegs()
- ADAMRTU_ReadInputStatus()
- ADAMRTU_ModServer_Create()
- Ver_RTU_Mod()

5.2.5 Category E: MODBUS/TCP Functions (MBTCP*.LIB)

- Ver_TCP_Mod()

**Modbus TCP Client Functions:**
- ReturnErr_code()
- ADAMTCP_Connect()
- ADAMTCP_Disconnect()
- ADAMTCP_ForceMultiCoils()
- ADAMTCP_ForceSingleCoil()
- ADAMTCP_PresetMultiRegs()
- ADAMTCP_PresetSingleReg()
- ADAMTCP_ReadCoilStatus()
- ADAMTCP_ReadHoldingRegs()
- ADAMTCP_ReadInputRegs()
- ADAMTCP_ReadInputStatus()

**Modbus TCP Server Functions:**
- ADAMTCP_ModServer_Create()
- ADAMTCP_ModServer_Update()
- ADAMTCP_ModServer_Release()
5.2.6 Category F: Socket Functions (SOCKET*.LIB)

**Socket function:**
- accept()
- bind()
- closesocket()
- connect()
- ioctlsocket()
- getpeername()
- getsockname()
- getsockopt()
- htonl()
- htons()
- inet_addr()
- inet_ntoa()
- listen()
- ntohl()
- ntohs()
- recv()
- recvfrom()
- select()
- send()
- sendto()
- setsockopt()
- shutdown()
- socket()

**Database function:**
- gethostbyaddr()
- gethostbyname()
- gethostname()
- getservbyport()
- getservbyname()
- getservbyportnumber()
- getprotobynumber()
5.2.7 Category G: HTTP Functions (CGI_LIB*.LIB)

Socket function:
HttpRegister()
HttpDeRegister()
HttpGetData()
HttpPostData()
HttpGetFile()
HttpPostFile()
HttpGetStatus()
HttpGetVersion()
GetStackPointer()
GetStackSegment()
SetStackPointer()
SetStackSegment()
Chapter 5 Programming and Function Library

5.3 Function Library Description

5.3.1 System Functions (UTILITY*.LIB)

adv_printf

Syntax:
void adv_printf(char *pFormat, ...);

Description:
Print string to console. This function has the same usage as printf() function. However, it has lower priority to be executed.

Parameter
The same as printf() of standard Borland C 3.0 library function.

Return value:
None.

Example:
#include "4500drv.h"
void main(void)
{
    adv_printf("Hello, this is for test.");
}

Remarks:
If printf() function is put within while loop such as Modbus/RTU server function, it will decrease the performance of server function due to higher priority of printf(). So it is strongly recommended that uses adv_printf() instead, which has lower priority than printf().
ADAMdelay

Syntax:
void ADAMdelay(unsigned short msec)

Description:
Delays program operation by a specified number of milliseconds.

Parameter | Description
-----------|-------------
msec       | From 0 to 65535.

Return value:
None.

Example:
#include "4500drv.h"
void main(void)
{
    /* codes placed here by user */
    ADAMdelay(1000); /* delay 1 sec. */
    /* codes placed here by user */
}

Remarks:
ADAMDelay will possibly decrease the performance so it is recommended to use for loop instead.
Get.BoardID

Syntax:
unsigned char Get.BoardID(void)

Description:
Gets the ID number of EB50 (built-in I/O board).

Parameter
None.

Return value:
The return value is the ID number of EB50 (built-in I/O board).

Remarks:
None.
Chapter 5 Programming and Function Library

Get_NodeID

Syntax:
unsigned char Get_NodeID(void)

Description:
Gets the ID number of the ADAM-4500 Series Controller.

Parameter
None.

Return value:
The ID number of the ADAM-4500 Series Controller.

Example:
#include "4500drv.h"
void main(void)
{
    int i, j;
    unsigned char   mID, found;
    adv_printf("\n Welcome to ADAM4500 PC-Based Controller\n");
    adv_printf("\n Scan I/O module ...\n");
    adv_printf("\n ADAM4500 NodeID = %02Xh", Get_NodeID() );
    /* Scan ADAM4500 Slot IO Module */
    mID = Get_BoardID();
    found=0;
    if( mID == EB50_ID)
    {
        adv_printf("\n Slot = EB50\n");
        found=1;
    }
    if(found == 0) adv_printf("\n Slot = None installed\n");
}

Remarks :
None
Chapter 5 Programming and Function Library

GetRTCtime
SetRTCtime

Syntax:
unsigned char GetRTCtime(unsigned char Time)
void SetRTCtime(unsigned char Time,unsigned char data)

Description:
GetRTCtime: Reads Real-Time Clock chip timer. A user can activate
 a program on the date desired.
SetRTCtime: Sets date and time of the real-time clock.

Parameter                   Description
Time          RTC_sec   the second
               RTC_min   the minute
               RTC_hour  the hour
               RTC_day   the day
               RTC_week  day of the week
               RTC_month the month
               RTC_year  the year

data           New contents.

Return value:
The value requested by the user.

Example:
#include "4500drv.h"
void main(void)
{unsigned char sec=0,min=0,hour=12;
  adv_printf("Time  %02d:%02d:%02d\n",GetRTCtime(RTC_hour),
               GetRTCtime(RTC_min), GetRTCtime(RTC_sec));
  adv_printf("Set current time 12:00:00\n");
  SetRTCtime(RTC_sec,sec);
  SetRTCtime(RTC_min,min);
  SetRTCtime(RTC_hour,hour);
  adv_printf("Time  %02d:%02d:%02d\n",GetRTCtime(RTC_hour),
               GetRTCtime(RTC_min), GetRTCtime(RTC_sec));
}

Remarks:
None.
Chapter 5 Programming and Function Library

**LED_init**  
**LED_OFF**  
**LED_ON**

**Syntax:**
void LED_init(void)  
void LED_OFF(int which_led)  
void LED_ON(int which_led)

**Description:**
Turns LED lights on and off. The LED I/O port must be initialized first. It will take a little time for the light to stabilize following the signal for the turning on and turning off of the light.

**Parameter:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>which_led</td>
<td>PWR</td>
<td>The PWR LED</td>
</tr>
<tr>
<td></td>
<td>RUN</td>
<td>The RUN LED</td>
</tr>
<tr>
<td></td>
<td>COMM</td>
<td>The COMM LED</td>
</tr>
</tbody>
</table>

**Return value:**
None.

**Example:**
#include "4500drv.h"
void main(void)  
{
    LED_init();  
    /* flash COMM led */  
    while(1)  
    {
        LED_ON(COMM);  
        ADAMdelay(500);  
        LED_OFF(COMM);  
    }
}

**Remarks:**
None.
Chapter 5 Programming and Function Library

**EraseSector**

**ProgramByte**

**ProgramSector**

**Syntax:**

- unsigned short EraseSector( unsigned long ulBase )
- unsigned short ProgramByte( unsigned long ulAddress, BYTE byte )
- unsigned short ProgramSector( unsigned long ulAddress_s, unsigned char far * SECTOR_DATA)

**Description:**

- **EraseSector:** Erases a 64 KB sector of data in the 256 KB Flash memory.
- **ProgramByte:** Programs a byte of information into the 256 KB Flash memory. This feature supports data-logging or mass information storage.
- **ProgramSector:** Programs an entire 32 KB sector of data of the global variable, SECTOR_DATA[], into 256 KB Flash memory.

**Parameter Description**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ulBase</td>
<td>User-determined address range to be erased, taken from addresses in the range 0x80000L to 0xB0000L.</td>
</tr>
<tr>
<td>ulAddress</td>
<td>User-determined destination address for byte transfer, taken from the range 0x80000L to 0xBFFFFL.</td>
</tr>
<tr>
<td>byte</td>
<td>The data user wants to write into the specific byte in the Flash memory.</td>
</tr>
<tr>
<td>ulAddress_s</td>
<td>User-determined destination address in the Flash memory, taken from addresses in the range 0x80000L to 0xB8000L.</td>
</tr>
<tr>
<td>SECTOR_DATA</td>
<td>Pointer at the starting address in the origin memory of the user's data array.</td>
</tr>
</tbody>
</table>

**Return value:**

- 1 Successful transfer to Flash memory.
- 0 Error (destination already occupied, excess address range, or program error).
read_mem

Syntax:
unsigned char read_mem (int memory_segment , unsigned int i)

Description:
Reads far memory data, 256 KB Flash memory, from 0x80000L to 0xBFFFFL, where (the Absolute Address) = (SEG*16 + OFFSET). For example, (0x800FFL) = (0x8000*16 + 0x00FF).

Parameter Description

<table>
<thead>
<tr>
<th>memory_segment</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>User-determined address taken from the range 0x8000 to 0xBF00.</td>
<td></td>
</tr>
</tbody>
</table>

| i | Offset for use in location of memory taken from the range 0x0000 to 0x0FFF. |

Return value:
The value in memory storage at the indicated address.

Example:
#include "4500drv.h"
void main(void)
{
    unsigned char sector[32768];
    unsigned char data;
    unsigned long addr,sector_num;
    unsigned int i;

    adv_printf("erase sector 0x80000L\n");
    if(EraseSector(0x80000L))
    adv_printf("erase succeed \n");
    adv_printf("Write data(55) to 0x80000~0x80001\n");
data=55;
    ProgramByte(0x80000L,data);
    ProgramByte(0x80000L+1,data);
    ProgramByte(0x80000L+2,data);
    for(i=0;i<3;i++)
    {
        adv_printf("read%d data=%d\n",i,read_mem(0x8000,0x0000+i));
    }
}
Chapter 5 Programming and Function Library

adv_printf("erase sector 0x80000L\n");
if(EraseSector(0x80000L))
adv_printf("erase succeed \n");
data = 1;
for(i=0;i<32768;i++)
    *(sector+i)=data;
adv_printf("Write data(0x01) to 0x80000~0x87FFF\n");
ProgramSector(0x80000,&sector);
for(i=0;i<100;i++)
{
    adv_printf("read%d data=%d\n",i,read_mem(0x8000,0x0000+i));
}

Remarks:
None.
Get_SysMem
Set_SysMem

Syntax:
unsigned char Get_SysMem(unsigned char which_byte)
void Set_SysMem(unsigned char which_byte, unsigned char data)

Description:
Get_SysMem: Reads a byte from security SRAM.
Set_SysMem: Writes a byte to security SRAM. Security SRAM supports 113 bytes for user storage of important information.

Parameter Description

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>which_byte</td>
<td>From 0 to 112, user-determined.</td>
</tr>
<tr>
<td>data</td>
<td>Value to be saved.</td>
</tr>
</tbody>
</table>

Return value:
Get_SysMem: Get the value in a byte of security SRAM.
Set_SysMem: None.

Example:
#include "4500drv.h"
void main(void)
{
    unsigned char data[4] = {1,2,3,4};
    int i;
    /* save current value */
    for(i=10;i < 14;i++)
    {
        Set_SysMem(i, data[i-10]);
        adv_printf("data=%d\n",Get_SysMem(i));
    }
}

Remarks:
None
Get_NVRAM_Size
Set_NVRAM_Size

Syntax:
unsigned char Get_NVRAM_Size(void)
void Set_NVRAM_Size(unsigned char sector)

Description:
Get_NVRAM_Size: Gets the size of battery backup RAM.
Set_NVRAM_Size: Sets the size of battery backup RAM.
(The unit is sectors, each sector is 4KB in size. Maximum size is 384
KB theoretically.)

Parameter Description
sector NVRAM size in 4 KB sectors, from 1 to 96 sectors.

Return value:
Get_NVRAM_Size: sector Number of sectors NVRAM size is set to,
from 1 to 96.
Set_NVRAM_Size: None.

Example:
#include "4500drv.h"
void main()
{
  unsigned char sector;
  sector = Get_NVRAM_Size();
  adv_printf("Backup ram=%dKbyte\n",sector*4);
  /*Set Bacup ram 40Kbyte*/
  Set_NVRAM_Size(10);
}

Remarks:
None.
write_backup_ram
read_backup_ram

Syntax:
void write_backup_ram(unsigned long index, unsigned char data)
unsigned char read_backup_ram(unsigned long index)

Description:
write_backup_ram: Writes a byte to battery backup memory.
read_backup_ram: Reads the value in backup RAM at index address,
maximum 384 KB total backup RAM, index = 0 – 393214

Parameter Description
index An index for data in the battery backup RAM, from 0
to 393214; maximum 384 KB battery backup
SRAM
in total.
data A byte of data that the programmer wants to write to
battery-protected SRAM.

Return value:
write_backup_ram: None.
read_backup_ram: The single-byte value in backup RAM at address
index.

Example:
#include "4500drv.h"
void main()
{
    unsigned long addr;
    unsigned char data;
    /*write the data 0x55 into battery backup memory, index=10*/
data=0x55;
    write_backup_ram(10,data);
    adv_printf("data=%x\n",read_backup_ram(10));
}

Remarks:
None
Timer_Init

Syntax:
int Timer_Init()

Description:
Initializes the timer built into the 80188 microprocessor. The return value "0" means the initialization of the time was successful. The return value "1" means the timer had already been initialized.

Parameter
None.

Return value:
0: Initialization was successful.
1: The timer had already been initialized.

Remarks:
None.

Example:
Refer to Release_All
Timer_Reset

Syntax:
void Timer_Reset(int idx)

Description:
Reset the timer identified by the integer idx to its initial state.

Parameter | Description
-----------|-------------
idx        | Timer index. (Timer ID)

Return value:
None.

Remarks:
None.

Example:
Refer to Release_All
Timer_Set

Syntax:
int Timer_Set(unsigned int msec)

Description:
Requests a timer from the microprocessor and then sets the time interval of the function. Timer intervals are set in 5 millisecond increments. The function return value is an integer representing the ID of the timer function when it is successful. A return value “-1” means the request failed. Programmers should consider whether an assigned timer has timed-out when programming for timer functions. The value of the variable \texttt{tmArriveCnt[idx]} (where \texttt{idx} is the timer ID) can be checked to verify timer status. Value of 0 indicates that the timer is still counting. Values other than 0 mean the timer has timed-out.

Parameter Description

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>msec</td>
<td>Time interval set, max. value is 65536</td>
</tr>
</tbody>
</table>

Return value:

<table>
<thead>
<tr>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0~100</td>
<td>Function Succeed. Value represents the timer ID.</td>
</tr>
<tr>
<td>-1</td>
<td>Function failure.</td>
</tr>
</tbody>
</table>

Remarks:
Timer function calls in the ADAM-4500 Series are emulated as timer functions in a PLC. Applications using timer functions will run less efficiently if the more timer functions are running simultaneously in a program.

Example:
Refer to \textit{Release_All}
Chapter 5 Programming and Function Library

Release_All

**Syntax:**
void Release_All()

**Description:**
Releases all timer resources of the ADAM-4500 Series system.

**Parameter**
None.

**Return value:**
None.

**Remarks:**
None.

**Example:**

```c
#include "4500drv.h"

void main()
{
    int idx;
    /* Initializes the timer built into the 80188 microprocessor */
    Timer_Init();
    /* Sets time interval of the timer to 1 second. */
    idx=Timer_Set(1000);
    /* Checks whether the timer has timed out */
    while(tmArriveCnt[idx]==0)
    {
        /* user can attend to other tasks... */
        adv_printf("test");
    }
    /* Resets the current timer to its initial state. */
    Timer_Reset(idx);
    /* Releases all timer resources */
    Release_All();
}
```
Chapter 5 Programming and Function Library

WDT_clear
WDT_disable
WDT_enable

Syntax:
void WDT_clear(void)
void WDT_disable(void)
void WDT_enable(void)

Description:
WDT_clear: Clear watchdog timer.
WDT_disable: Disable watchdog timer.
WDT_enable: Enable watchdog timer.
When the watchdog timer is enabled, it will have to be cleared at least once every 1.6 seconds, or the system will automatically reboot. The watchdog timer default value is “disable”.

Parameter
None.

Return value:
None.

Example:
#include "4500drv.h"
void main(void)
{
    int i;
    WDT_enable();
    for(i=0;i<100;i++)
    {
        /*put your code in Here*/
        WDT_clear();
        /*put your code in Here*/
    }
    WDT_disable();
}

Remarks:
None
**display_init**

**display_digit**

**Syntax:**
void display_init(unsigned char decode_mode)
int display_digit(unsigned char *data, unsigned char digit, unsigned char len)

**Description:**
7-segment display setting
Display_init: Initialize all 7-segment displays.
Display_digit: Writes the numeric into the all 7-segment displays.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>decode_mode</td>
<td>Decode mode. (0 is No decode, 1 is Code B decode)</td>
</tr>
<tr>
<td>data</td>
<td>The display value.</td>
</tr>
<tr>
<td>digit</td>
<td>There are five 7-segment LED displays. This parameter determines which display is the starting LED display. It can be 1~5.</td>
</tr>
<tr>
<td>len</td>
<td>Total number of LED displays you want to control.</td>
</tr>
</tbody>
</table>

**No Decode mode:**

![Diagram of 7-segment LED](image)

<table>
<thead>
<tr>
<th>REGISTER DATA</th>
</tr>
</thead>
<tbody>
<tr>
<td>D7</td>
</tr>
<tr>
<td>Corresponding Segment Line</td>
</tr>
</tbody>
</table>

The bit D0~D7 are the corresponding LED segment.
For example: data 30(hex) can show the “1” of the LED character. (D5/D4 are 1 and others are 0)
Chapter 5 Programming and Function Library

**Code B Decode mode:**

<table>
<thead>
<tr>
<th>7-SEGMENT CHARACTER</th>
<th>REGISTOR DATA</th>
<th>ON SEGMENTS + 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>D7**</td>
<td>D6-D4</td>
<td>D3</td>
</tr>
<tr>
<td>0</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>2</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>3</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>4</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>5</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>6</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>7</td>
<td>X</td>
<td>0</td>
</tr>
<tr>
<td>8</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>9</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>E</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>H</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>L</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>P</td>
<td>X</td>
<td>1</td>
</tr>
<tr>
<td>blank</td>
<td>X</td>
<td>1</td>
</tr>
</tbody>
</table>

*The decimal point is set by bit D7 = 1

Above this table, 7-SEGMENT CHARACTER is the value showed on LED displayed and REGISTOR DATA is setting value. When the bit D7 is “1” (bit4~bit6 can be arbitrary bumber), the value will be a decimal point.

For example: data 3(hex) can show the number “3” of the LED character. And data 83 can show the number “3.” of the LED character

**Return value:**
None.

**Example:**

Refer to C:\Program Files\Advantech\ADAM-4500 Series Utility \Source\Example\Basic_Function\ex1.C for this example

```c
#include "4500drv.h"
#include "dos.h"
```
void main(void) {
    unsigned char data[5] = {1,2,3,4,5} ;
    int i;

    display_init(1);
    printf("please input 5 numbers (0 - 9):\n");
    for (i=0; i<5 ;i++)
    {
        scanf("%d",&data[i]);
        if (data[i]<0 || data[i] > 9)
        {
            printf("input error, exit");
            exit(0);
        }
    }

    display_digit(&data,1,5);
    exit(0);
}

Remarks:
None.
BatteryStatus

Syntax:
int BatteryStatus(void)

Description:
Check the power status of battery which is used by battery backup SRAM.

Parameter
None.

Return value:
0 The power status of battery is almost run out. It is strongly recommend to change a new battery.
1 The power status of battery is still normal.

Example:
None.
Ver

Syntax:
void Ver(char *vstr)

Description:
Check Utility Library version.

Parameter Description
vstr Pointer to array of Utility Library version information

Return value:
None.

Example:

char library_ver[20];

void main(void)
{
    Ver(library_ver);
    
    adv_printf("The version of utility library is %s\n", library_ver);
}
5.3.2 I/O Module Functions  (HIO*.LIB)

InitDIFilter

Syntax:
void InitDIFilter(int iCh, unsigned int MIN_Lo_Width, unsigned int MIN_High_Width)

Description:
Set time interval of digital filter for DI channel.

Parameter Description
iCh Channel no. (0 ~ 4)
MIN_Lo_Width Time interval of DI filter for Low state. (5 ~ 65535 msec)
MIN_High_Width Time interval of DI filter for High state. (5 ~ 65535 msec)

Return Value:
None.

Remarks:
Reference Data:

<table>
<thead>
<tr>
<th>Time Interval</th>
<th>Cut-off Frequency</th>
</tr>
</thead>
<tbody>
<tr>
<td>15 ms</td>
<td>50 Hz</td>
</tr>
<tr>
<td>30 ms</td>
<td>20 Hz</td>
</tr>
<tr>
<td>50 ms</td>
<td>12 Hz</td>
</tr>
</tbody>
</table>
GetDIO (for DI only)
SetDO

Syntax:
UCHAR  GetDIO(UCHAR  i_ucModuleID,  UCHAR  i_ucMode,
UCHAR  i_ucChannel, ULONG * o_ulValue)
UCHAR  SetDO(UCHAR  i_ucModuleID,  UCHAR  i_ucMode,
UCHAR  i_ucChannel, ULONG i_ulValue)

Description:
Read/Write the value of digital input /output channels.

Parameter Description
i_ucModuleID Module ID.
i_ucMode SingleChannel or AllChannels.
i_ucChannel SingleChannel: the channel you use.
                           AllChannels: don't care.
o_ulValue DIO value read from module.
i_ulValue DIO value written to module.

Return Value:
If success, return 0. If fail, returns a negative number as follows:
   Illegal_Setting -5
   Board_Not_Exist -7

Remarks:
None

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Ver_HIOLib

Syntax:
void Ver_HIOLib(char *vstr)

Description:
Get HIO Library version.

Parameter | Description
-----------|-----------------
vstr       | Pointer to array of HIO Library version information.

Return value:
None.

Example:
char library_ver[20];

void main(void)
{
    Ver_HIOLib(library_ver);
    adv_printf("The version of library is %s\n", library_ver);
}

Remarks:
None.
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GetAI (for ADAM-4502 only)

Syntax:
CHAR GetAI(UCHAR i_ucMode, UCHAR i_ucChannel, LONG *o_lAIValue)

Description:
Get the value of analog input channel.

Parameter Description
i_ucMode Get AI mode : SingleChannel, AllChannels
i_ucChannel Channel index
o_lAIValue SingleChannel: AI value
AllChannels: AI values

Return Value:
On success, return UE_OK
On error, return ErrorCode

SetAO (for ADAM-4502 only)

Syntax:
CHAR SetAO(UCHAR i_ucChannel, ULONG i_ulValue)

Description:
Set the value of analog output channel.

Parameter Description
i_ucChannel Channel index
i_ulValue Set AO value

Return Value:
On success, return UE_OK
On error, return ErrorCode
Chapter 5 Programming and Function Library

SetAIRange (for ADAM-4502 only)

Syntax:
CHAR SetAIRange(UCHAR i_ucSetChannel,UCHAR i_ucSetRange);

Description:
Set the range of analog input channel.

Parameter Description
i_ucSetChannel       Channel index
i_ucSetRange          AI range code

Return Value:
On success, return UE_OK
On error, return ErrorCode

SetAORange (for ADAM-4502 only)

Syntax:
CHAR SetAORange(UCHAR i_ucSetChannel,UCHAR i_ucSetRange);

Description:
Set the range of analog output channel.

Parameter Description
i_ucSetChannel       Channel index
i_ucSetRange          AO range code

Return Value:
On success, return UE_OK
On error, return ErrorCode
SetAlSpeed (for ADAM-4502 only)

Syntax:

CHAR SetAlSpeed(UCHAR ucSettingSpeed);

Description:
Set the speed of analog input channel.

Parameter | Description
--------- |-----------
ucSettingSpeed | AIBandwidth60HZ, AIBandwidth50HZ

Return Value:
On success, return UE_OK
On error, return ErrorCode
Chapter 5 Programming and Function Library

DIO Example:

Refer to C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\Basic_Function\Ex2.C for this example

```
#include "4500drv.h"
void main()
{
    int tmpCnt=0;
    char c;
    unsigned char type;
    unsigned long div, dov;
    char Ver_Str[30];

    Ver_HIOLib(Ver_Str);
    printf("The HIO library version is %s\n", Ver_Str);

    /* ---- First scan for the existing IO modules -------*/
    type = Get_BoardID();

    /*----Show the module type of each slot on the screen ---*/
    if( type == EB50_ID)
        printf("IO slot is EB50\n");
    else
        printf("IO slot is Null\n");

    printf("press any key to continue...\n");getch();

    /*--- Digital I/O modules don't need to be initialized ---*/

    /*---- Forever loop until the user press any key */
    while(1)
    {
        tmpCnt++;
        /*---- Set DO Value ------*/
        printf("Set and Get All Channels Test:\n");
        if((tmpCnt%2)==0)
            dov=0;
        else
            dov=0xf;
        if(SetDO(EB50_ID, AllChannels, 0, dov)==0)
        {
            printf("Set DO value 0x%X, ", dov);
        }
        printf("Set DO value 0x%X, ", dov);
```

printf("press any key to continue..\n");getch();
if(GetDIO(EB50_ID, AllChannels, 0, &div)==0)
{
    printf("DI value is 0\x%X\n", div);
}
else
    printf("Get DI failed\n");
else
    printf("Set DO failed\n");

printf("\n\nSet and Get Sigle Channel Test:\n");
if((tmpCnt%2)==0)
    dov=0;
else
    dov=1;
if(SetDO(EB50_ID, SingleChannel, 1, dov)==0)
{
    printf("Set DO channel 1 value %x, ", dov);
    printf("press any key to continue..\n");getch();
    if(GetDIO(EB50_ID, SingleChannel, 1, &div)==0)
    {
        printf("Channel 1 DI value is %x\n", div);
    }
    else
        printf("Get DI failed\n");
}
else
    printf("Set DO failed\n");

printf("press 'Q' to quit, the other key to continue..\n");
c=getch();
if( c == 'q' || c == 'Q')
    break;
5.3.3 Communication Functions (A4_COMM*.LIB)

SIO_Open

Syntax:
CHAR SIO_Open(UCHAR i_ucPort)

Description:
Initializes the COM port and interrupt service routine before other function calls use the COM port.

Parameter Description
i_ucPort The Port number you want to initial (see remarks).

Return value:
If success, return 0. If fail, returns a negative number as follows:
COM_already_installed -1
Err_Access_COM -2
No_Such_Port -3

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
</tr>
<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
SIO_Close

Syntax:
CHAR SIO_Close(UCHAR i_ucPort)

Description:
Release resource of the specific COM port. If a user calls the
SIO_Open function, the user must call this function to release the
COM port before the user's program terminates.

Parameter Description
i_ucPort The Port number you want to release (see remarks).

Return value:
If success, return 0. If fail, returns a negative number as follows:
No_Such_Port -3

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td>COM2</td>
<td>COM2</td>
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<td>COM3</td>
<td>COM3</td>
<td></td>
</tr>
<tr>
<td>COM4</td>
<td>COM4</td>
<td></td>
</tr>
</tbody>
</table>
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SIO_SetState

Syntax:
CHAR SIO_SetState(UCHAR i_ucPort, ULONG i_ulBaudRate, 
UCHAR i_ucParity, UCHAR i_ucDataBits, UCHAR i_ucStopBits)

Description:
Sets the parameters such as baud rate, parity, data bits and stop bits for the specific COM port.

Parameter Description
i_ucPort The Port number you want to use (see remarks).
i_ulBaudRate The Baud Rate number you want to set up.
i_ucParity The Parity you want to set up (see remarks).
i_ucDataBits The data bits you want to set up (see remarks).
i_ucStopBits The stop bits you want to set up (see remarks).

Return value:
If success, return 0. If fail, return a negative number as follows:
No_Such_Port -3
COM_Not_Installed -4
Illegal_Setting -5

Remarks:
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
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<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
<tr>
<td>i_ucParity</td>
<td>NO_PARITY (0x00)</td>
<td>No parity</td>
</tr>
<tr>
<td></td>
<td>ODD_PARITY (0x08)</td>
<td>Odd parity</td>
</tr>
<tr>
<td></td>
<td>EVEN_PARITY (0x18)</td>
<td>Even Parity</td>
</tr>
<tr>
<td>i_ucDataBits</td>
<td>DATA5 (0x00)</td>
<td>5 Data Bits</td>
</tr>
<tr>
<td></td>
<td>DATA6 (0x01)</td>
<td>6 Data Bits</td>
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<tr>
<td></td>
<td>DATA7 (0x02)</td>
<td>7 Data Bits</td>
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<tr>
<td></td>
<td>DATA8 (0x03)</td>
<td>8 Data Bits</td>
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<tr>
<td>i_ucStopBits</td>
<td>STOP1 (0x00)</td>
<td>1 Stop Bits</td>
</tr>
<tr>
<td></td>
<td>STOP2 (0x04)</td>
<td>2 Stop Bits</td>
</tr>
</tbody>
</table>
Chapter 5 Programming and Function Library

SIO_RecvBytes

Syntax:
INT   SIO_RecvBytes(UCHAR   i_ucPort,   UCHAR   i_ucMode, 
UINT i_uinBytes, UCHAR * o_ucDataBuf)

Description:
This function call is employed to received string data from the specific 
COM port. On success, this function call returns the total 
bytes has been read from the specific COM port. On fail, function 
call returns a negative value as error code.

Parameter Description
i_ucPort       The Port number you want to use (see remarks).
i_ucMode      Decide to use Block mode or UnBlock mode.  
              (When using Block mode, program will block 
              here until i_uinBytes data is received. When using 
              UnBlock 
              mode, program will not block and return 
              the total 
              number of bytes data have been received directly.)
i_uinBytes   Number of bytes to be read.
o_ucDataBuf  A buffer for received data.

Return value:
If success, returns the total number of bytes read. If fail, return a negative number as follows:
No_Such_Port    -3
Illegal_Setting -5
RequestOverQueueSize -6

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
</tr>
<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
<tr>
<td>i_ucMode</td>
<td>Block_Mode (0x01)</td>
<td>Block mode</td>
</tr>
<tr>
<td></td>
<td>UnBlock_Mode (0x02)</td>
<td>UnBlock mode</td>
</tr>
</tbody>
</table>
SIO_SendBytes

Syntax:
INT SIO_SendBytes(UCHAR i_ucPort, UINT i_uinBytes, 
UCHAR * i_ucDataBuf)

Description:
To send character(s) to a specified COM port.

Parameter Description
i_ucPort The Port number you want to send (see remarks).
i_uinBytes Number of bytes to be sent.
i_ucDataBuf A buffer for sending data.

Return value:
If success, return the number of bytes have been sent. If fail, return a 
negative number as follows
No_Such_Port -3

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
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<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
SIO_GetAvaiRecvBytes
SIO_GetAvaiSendBuf

Syntax:
INT SIO_GetAvaiRecvBytes(UCHAR i_ucPort)
INT SIO_GetAvaiSendBuf(UCHAR i_ucPort)

Description:
SIO_GetAvaiRecvBytes: Returns the number of bytes in input buffer.
SIO_GetAvaiSendBuf: Returns the number of bytes in output buffer.

Parameter Description
i_ucPort The Port number you want to use (see remarks).

Return value:
SIO_GetAvaiRecvBytes: If success, return the number of bytes data in input buffer. If fail, return a negative number as follows
  No_Such_Port -3
SIO_GetAvaiSendBuf: If success, return the number of remaining available bytes space in output buffer. If fail, return a negative number as follows
  No_Such_Port -3

Remarks:
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
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<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
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<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
**Chapter 5 Programming and Function Library**

**SIO_PurgeBuf**

**Syntax:**
CHAR SIO_PurgeBuf(UCHAR i_ucPort, UCHAR i_ucFlag)

**Description:**
User can clear input buffer and output buffer together with argument 
i_ucFlag.

**Parameter** | **Description**  
--- | ---  
i_ucPort | The Port number you want to use (see remarks).  
i_ucFlag | Decide which buffer you want to clear. You can choose to clear input buffer or output buffer (see remarks).

**Return value:**
If success, return 0. If fail, return a negative number as follows:
- **No_Such_Port** -3
- **Illegal_Setting** -5

**Remarks:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>COM2</td>
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<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
<tr>
<td>i_ucFlag</td>
<td>Clear_RXBuffer (0x01)</td>
<td>Clear input buffer</td>
</tr>
<tr>
<td></td>
<td>Clear_TXBuffer (0x02)</td>
<td>Clear output buffer</td>
</tr>
</tbody>
</table>
Chapter 5 Programming and Function Library

COM Port Communication Example 1:

Refer to C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\Basic_Function\ExCOM.C for this example

ifdef Product_5510
    #include "5510drv.h"
#else defined Product_4500
    #include "4500drv.h"
#endif

#include <conio.h>
#include <dos.h>

#define DataLen50
#define RecvDataLen 30

void main()
{
    UCHAR tmpCOM, Idx=0;
    CHAR Data[DataLen];
    UCHAR Mode=0; //0=>Receive, 1=>Send
    CHAR VerStr[30];
    UCHAR RecvMode;
    UCHAR nByte=0, nTotalByte=0;

    printf("Arthur New COM Port Library Test 3.3\n");
    printf("=================================\n");
    Ver_COMLib(VerStr);
    printf("Com Library Version: %s\n", VerStr);
    printf("Enter receive mode( 1: Block mode, 0: unBlock mode):\n");
    scanf("%d", &tmpCOM);
    if(tmpCOM==0)
        RecvMode=UnBlock_Mode;
    else
        RecvMode=Block_Mode;

ifdef Product_5510

    printf("Enter COM port selection( 1: COM1, 2: COM2, 3: COM4)\n");

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```c
#include "stdio.h"

int main()
{
    int tmpCOM;

    printf("Enter COM port selection( 1: COM1, 2: COM2, 3: COM3, 4: COM4)");
    scanf("%d", &tmpCOM);
    if(tmpCOM==1)
    
    else if(tmpCOM==2)
    
    else if(tmpCOM==3)
    
    else if(tmpCOM==4)
    
    else
    
    printf("Wrong selection!
");
    return;

    printf("Opening COM Port with 57600 baud...
");

    if(SIO_Open(tmpCOM)!=0)
    
    if(SIO_SetState(tmpCOM, (unsigned long)57600, NO_PARITY, DATA8, STOP1)!=0)
    
    return;

    return;
}
```

**Chapter 5 Programming and Function Library**

```c
scanf("%d", &tmpCOM);
if(tmpCOM==1)
    tmpCOM=COM1;
else if(tmpCOM==2)
    tmpCOM=COM2;
else if(tmpCOM==3)
    tmpCOM=COM3;
else if(tmpCOM==4)
    tmpCOM=COM4;

#elf defined Product_4500

    printf("Enter COM port selection( 1: COM1, 2: COM2, 3: COM3, 4: COM4)");
    scanf("%d", &tmpCOM);
    if(tmpCOM==1)
        tmpCOM=COM1;
    else if(tmpCOM==2)
        tmpCOM=COM2;
    else if(tmpCOM==3)
        tmpCOM=COM3;
    else if(tmpCOM==4)
        tmpCOM=COM4;

    printf("Wrong selection!
");
    return;

    printf("Opening COM Port with 57600 baud...
");

    if(SIO_Open(tmpCOM)!=0)
    
    printf("error\n");
    return;

    printf("Set State Error\n");
    return;
```
SIO_PurgeBuf(tmpCOM, Clear_RXBuffer);
SIO_PurgeBuf(tmpCOM, Clear_TXBuffer);

while(1)
{
    if(Mode==0)
    {
        if(RecvMode==Block_Mode)
        {

            if(SIO_GetAvaiRecvBytes(tmpCOM)>=RecvDataLen)
            {
                if(SIO_RecvBytes(tmpCOM, Block_Mode, RecvDataLen, Data)==RecvDataLen)
                {
                    if(Data[RecvDataLen-1]==0x0d)
                    {
                        Mode=1;
                        Idx=0;
                    }
                    else
                    {
                        printf("Error
Receive\n");
                        return;
                    }
                }
            }
            else
            {
                printf("Error
Receive\n");
                return;
            }
        }
        else
        {
            printf("Error
Receive\n");
            return;
        }
    }
    else
    {
        //do something else here
    }
}
else if(RecvMode==UnBlock_Mode)
{
    while(nTotalByte<RecvDataLen)
    {
        if((nByte=SIO_RecvBytes(tmpCOM, UnBlock_Mode,
                       RecvDataLen, &Data[nTotalByte]))>=0)
        {
            nTotalByte+=nByte;
        }
        else
        {
            printf("Error
Receive\n");
            return;
        }
    }
    Mode=1;
    Idx=0;
    nTotalByte=0;
}
else
{
    if(SIO_GetAvaiSendBuf(tmpCOM)>=RecvDataLen)
    {
        if(SIO_SendBytes(tmpCOM,
                         RecvDataLen, Data)==RecvDataLen)
        {
            Idx=RecvDataLen;
            if(Data[Idx-1]==0x0d)
            {
                Mode=0;
                Idx=0;
            }
        }
    }
}
else
{
    printf("Error Send\n");
    return;
}
} else
{
    printf("do something send\n");
    //do something else...
}
}
SIO_Close(tmpCOM);
}
SIO_MakeCheckSum

Syntax:
UINT SIO_MakeCheckSum(UCHAR * i_ucDataBuf, UINT i_uiLen)

Description:
Calculates the checksum of the string or data array (i_ucDataBuf).

Parameter | Description
----------|------------------
i_ucDataBuf | The string or data array for which a user wants to calculate the checksum.
i_uiLen | The length of the string or the data array.

Return value:
The checksum value of the data array buffer

Remarks:
None.
SIO_MakeCRC16

Syntax:
UINT SIO_MakeCRC16(UCHAR * i_ucDataBuf, UINT i_uiLen)

Description:
Calculates the CRC 16-bit value of the string (i_ucDataBuf).

Parameter Description
i_ucDataBuf The string which you want to calculate CRC code.
i_uiLen The length of string (i_ucDataBuf).

Return value:
The CRC16 code.

Remarks:
None.
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SIO_Carrier

Syntax:
CHAR SIO_Carrier(UCHAR i_ucPort)

Description:
Detects the carrier signal of the specific COM port.

Parameter Description
i_ucPort The Port number you want to use (see remarks).

Return value:
If success, return TRUE(1). If fail, return a non-positive number as follows:
FALSE 0
Illegal_Setting -5

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
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<td>COM2</td>
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</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
## Chapter 5 Programming and Function Library

### SIO_ClearBreak

**Syntax:**
CHAR SIO_ClearBreak(UCHAR i_ucPort)
CHAR SIO_SetBreak(UCHAR i_ucPort)

**Description:**
- **SIO_ClearBreak**: Sets the specific COM port to clear BREAK signal.
- **SIO_SetBreak**: Sets the specific COM port to send BREAK signal.

**Parameter** | **Description**
--- | ---
**i_ucPort** | The Port number you want to use (see remarks).

**Return value:**
- If success, return 0.
- If fail, return a negative number as follows:
  - **Illegal_Setting**: -5

**Remarks:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
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<tr>
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<td>COM1</td>
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<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
**Chapter 5 Programming and Function Library**

**SIO_GetLineStatus**  
**SIO_SetLineParams**  
**SIO_GetModemStatus**

**Syntax:**  
CHAR SIO_GetLineStatus(UCHAR i_ucPort)  
CHAR SIO_SetLineParams(UCHAR i_ucPort, UCHAR i_ucParams)  
CHAR SIO_GetModemStatus(UCHAR i_ucport)

**Description:**  
SIO_GetLineStatus: Reads line control register of specific COM port.  
SIO_SetLineParams: Writes to line control register of specific COM port.  
SIO_GetModemStatus: Reads modem status register of specific COM port.

**Parameter**  
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>The Port number you want to use (see remarks).</td>
</tr>
<tr>
<td>i_ucParams</td>
<td>UART register parameter (refer to Appendix A for the 16C550 UART register document).</td>
</tr>
</tbody>
</table>

**Return value:**  
If success, return the UART register value (refer to Appendix A for the 16C550 UART register document). If fail, return a negative number as follows:  
- Illegal_Setting -5

**Remarks:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
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<td>COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
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</tr>
<tr>
<td></td>
<td>COM3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>COM4</td>
</tr>
</tbody>
</table>
SIO_LowerRaise_RTS_DTR

Syntax:
CHAR SIO_LowerRaise_RTS_DTR(UCHAR i_ucPort, UCHAR i_ucL_R_Mode, UCHAR i_ucSignal)

Description:
Lower or raise the RTS/DTR signal.

Parameter Description
i_ucPort The Port number you want to use (see remarks).
i_ucL_R_Mode Decide to raise or lower signal (see remarks).
i_ucSignal Decide to set RTS or DTR signal (see remarks).

Return value:
If success, return 0. If fail, return a negative number as follows:
Illegal_Setting -5

Remarks:
<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
<tr>
<td>i_ucL_R_Mode</td>
<td>RaiseSignal (0x01)</td>
<td>Raise signal</td>
</tr>
<tr>
<td></td>
<td>LowerSignal (0x02)</td>
<td>Lower signal</td>
</tr>
<tr>
<td>i_ucSignal</td>
<td>Signal_RTS (0x01)</td>
<td>RTS signal</td>
</tr>
<tr>
<td></td>
<td>Signal_DTR (0x02)</td>
<td>DTR signal</td>
</tr>
</tbody>
</table>
SIO_ModemInitial

Syntax:
CHAR SIO_ModemInitial(UCHAR i_ucPort)

Description:
Sets modem to initial status. Due to the ADAM-4500 Series system’s construction, the modem can only be connected to COM1. This function resets the modem to the initial state. The command has the same effect as sending the ASCII command “atz” to the modem.

Parameter Description
i_ucPort The Port number you want to use (see remarks).

Return value:
If success, return 0. If fail, return a negative number as follows:
Illegal_Setting -5

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
SIO_ModemAutoanswer

Syntax:
CHAR SIO_ModemAutoanswer(UCHAR i_ucPort)

Description:
Sets up modem to auto answer phone calls.

Parameter | Description
-----------|----------------
i_ucPort   | The Port number you want to use (see remarks).

Return value:
If success, return 0. If fail, return a negative number as follows:
Illegal_Setting -5

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
Chapter 5 Programming and Function Library

SIO_ModemCommand

Syntax:
CHAR SIO_ModemCommand(UCHAR i_ucPort, UCHAR * i_ucCmdStr)

Description:
Sends an AT command string to the modem. For details, refer to the AT command document provided by the manufacturer.

Parameter Description
i_ucPort The Port number you want to use
i_ucCmdStr Specifies command string, please refer to the AT command document

Return value:
If success, return 0. If fail, return a negative number as follows
Illegal_Setting -5

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
SIO_ModemCommand_State

Syntax:
CHAR SIO_ModemCommand_State(UCHAR i_ucPort)

Description:
Sets modem to command mode. In other words, this causes the modem to escape from data mode to command mode. The modem will delay at least 3 seconds before switching back to command mode. This command has the same effect as sending the ASCII command “+++” to the modem.

Parameter | Description
---|---
i_ucPort | The Port number you want to use (see remarks).

Return value:
If success, return 0. If fail, return a negative number as follows:
Illegal_Setting -5

Remarks:

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
**SIO_ModemDial**

**Syntax:**
CHAR SIO_ModemDial(UCHAR i_ucPort, UCHAR * i_ucTelenum)

**Description:**
Directs modem to connect to the specified telephone number.

**Parameter Description**
- **i_ucPort**: The Port number you want to use (see remarks).
- **i_ucTelenum**: The phone number you would like modem to dial.

**Return value:**
If success, return 0. If fail, return a negative number as follows:
- **Illegal_Setting**: -5

**Remarks:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
**SIO_ModemHandup**

**Syntax:**
CHAR SIO_ModemHandup(UCHAR i_ucPort)

**Description:**
Sets the modem to hand up the telephone. The command has the same effect as sending the ASCII command “atho” to the modem.

**Parameter Description**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>The Port number you want to use (see remarks).</td>
</tr>
</tbody>
</table>

**Return value:**
If success, return 0. If fail, return a negative number as follows:
- **Illegal_Setting** -5

**Remarks:**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>i_ucPort</td>
<td>COM1</td>
<td>COM1</td>
</tr>
</tbody>
</table>
#include "4500drv.h"

int get_modem_response(char *buf)
{
    long i;
    int index;
    unsigned char c;

    index=0;
    for(i=0;i<10000; i++)
    {
        /*--- Get the receiving string from the COM1 port ---*/
        if(SIO_RecvBytes(COM1, UnBlock_Mode, 1, &c)>0)
            buf[index++]=c;

        if( index >0  && c == '\r') /* end of command */
        {
            buf[index] =0;
            adv_printf("Response : %s ",buf);
            return(1);
        }
    }

    return(0);
}

void main()
{
    char   c;
    int result_code;
    char   buf[131]; int index;
    long   i;
    long   retry;

    SIO_ModemInitial(COM1);
}
while(1)
{
    adv_printf("----------- Main Menu ----------\n");
    adv_printf("0: Exit. \n");
    adv_printf("1: COM port setting. \n");
    adv_printf("2: Dial. \n");
    adv_printf("3: Set to auto-answer. \n");
    adv_printf("4: Set BREAK. \n");
    adv_printf("5: Hand up. \n");
    adv_printf("\n Please select a item to implement...\n");
    c=getch();
    switch(c)
    {
    case '0':
        return;
    case '1':
        /*--- Install the interrupt service routine for COM1---*/
        if(SIO_Open(COM1)!=0)
        {
            printf("error\n");
            return;
        }
        if(SIO_SetState(COM1, (unsigned long)9600,
                        NO_PARITY, DATA8, STOP1)!=0)
        {
            printf("Set State Error\n");
            return;
        }
        /*--- Show the data format on the screen ---*/
        adv_printf("COM port is COM1, baud rate is 9600 bps,
                    data format is N,8,1\n");
        break;
    case '2':
        /*--- Send prefix ---*/
        SIO_ModemCommand(COM1, "AT");
        /*--- Wait about 1 second---*/
        retry=100000;
        for(i=0;i<retry;i++)
        {
            i++;i--;
        }
    }
/*--- Clear the buffers of the transmitter and receiver---*/
SIO_PurgeBuf(COM1, Clear_RXBuffer);
SIO_PurgeBuf(COM1, Clear_TXBuffer);
/**--- Start to dial ---*/
/**--- Set DTR is ON(1). ---*/
SIO_LowerRaise_RTS_DTR(COM1, RaiseSignal, Signal_DTR);
/*--- Send the dialing command and phone number ---*/
sprintf(buf,"886222184867");
SIO_ModemDial(COM1, buf);
adv_printf("Command : %s \n",buf);
/*--- Wait for the response from the other end ---*/
if( get_modem_response(buf)== 1)
    adv_printf("Response : %s \n",buf);
else
    adv_printf("Response : %s \n","No response");
break;

case '3':
/*--- After one ring-bell, the phone is answered automatically. ---*/
SIO_LowerRaise_RTS_DTR(COM1, RaiseSignal, Signal_DTR);
SIO_ModemAutoanswer(COM1);
adv_printf("Now is ready to get data...\n");
break;

case '4':
/* Set Break */
SIO_SetBreak(COM1);
adv_printf("Now set a break to modem...\n\n\n");
/*--- Wait about 0.3 second---*/
retry=30000; for(i=0;i<retry;i++)
{
    i++;i--;
}
SIO_ClearBreak(COM1);
adv_printf("Now clear the break ...\n\n\n");
break;
case '5':
  /*--- Set DTR line OFF ---*/
  SIO_LowerRaise_RTS_DTR(COM1, LowerSignal,
    Signal_DTR);
  /*--- Wait about 0.3 second ---*/
  retry=30000; for(i=0;i<retry;i++)
  {
    i++;i--;
  }
  /*--- Check whether DCD is off ---*/
  /* if(!(com_get_modem_status(0x3F8)&0x80))
    break; 
  */
  /*--- Go to modem command state ---*/
  SIO_ModemHandup(COM1);
  retry=3;
  do{
    SIO_ModemHandup(COM1);
    if( get_modem_response(buf)== 1)
    {
      if( buf[0] ==0)
        break;
      adv_printf("retry %ld \n",4-retry);
    }
    adv_printf("retry %ld \n",4-retry);
  }while(--retry);
  adv_printf("Now is hand up...\n");
  break;
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Ver_COMLib

Syntax:
void Ver_COMLib(char *vstr)

Description:
Get COM Port Library version.

Parameter | Description
--- | ---
vstr | Pointer to array of COM Port Library version information.

Return value:
None.

Example:
char library_ver[20];

void main(void)
{
    Ver_COMLib(library_ver);
    adv_printf("The version of library is %s\n", library_ver);
}

Remarks:
None.
5.3.4 MODBUS/RTU Functions (RTU*.LIB)

Before using Modbus Functions, please read the Modbus Quick Start below to understand how to use Modbus libraries:

**Quick Start of MBTCP.Lib and MBRTU.Lib**

Only two steps are needed to create a server or make a client query.

**How to Create a Modbus TCP/RTU Server?**

**Modbus RTU Server:**
Step 1: Use `Modbus_COM_Init(...)` function to initialize a COM port for Modbus RTU Server.
Step 2: Use `ADAMRTU_ModServer_Create(...)` to create Modbus RTU Server.

**Modbus TCP Server:**
Step 1: Use `ADAMTCP_ModServer_Create(...)` function to create a Modbus TCP server.
Step 2: Call `ADAMTCP_ModServer_Update(...)` function periodically to check if there is any client message and keep the server alive.

**How to Create a Modbus TCP/RTU Client?**

**Modbus RTU Client:**
Step 1: Use `Modbus_COM_Init(...)` function to initialize a COM port for Modbus RTU Client.
Step 2: Use `ADAMModbusRTU_Read(...)` to query data from server or use `ADAMModbusRTU_Write(...)` to write data to server.

**Modbus TCP Client:**
Step 1: Use `ADAMTCP_Connect(...)` to make a connection to server.
Step 2: Use `ADAMModbusTCP_Read(...)` to query data from server or use `ADAMModbusTCP_Write(...)` to write data to server.

**Example: (Modbus RTU Server and Modbus RTU client)**

Assume that we now need a Modbus RTU Server with valid address in the range of 40001-40008. Before starting to create a server, we need to define the slave ID for server.

```
#define SlaveID 1
```

---

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And second, we need to allocate a physical memory for address 40001-40008:

```c
```

Finally, we can create a server. The COM1 and Slave are used to specify that the COM1 is used as slave mode and dedicated for server use.

```c
Modbus_COM_Init(COM1, Slave, (unsigned long)9600, NO_PARITY, DATA8, STOP1);
ADAMRTU_ModServer_Create(SlaveID, (unsigned char*) ModbusAddr_Mem, sizeof(ModbusAddr_Mem));
```

But, how do we put the data to the address 40001-40008 for client queries? Just simply put any data you want to the physical memory:

```c
ModbusAddr_Mem[0] = 0x1234; // 40001 => 0x1234
ModbusAddr_Mem[7] = 0x4321; // 40008 => 0x4321
```

OK, we've learned the techniques of creating a server. Now, let's see how to make query to get data at 40001-40008 from server. First, define some needed information for querying server.

```c
#define Read_StartAddr 40001 // query data start from address 40001
#define Read_EndAddr 40008 // query data end to address 40008
#define SlaveID 1
```

Second, we need to allocate a physical memory for query data.

```c
unsigned char Resp_From_Server[16];
// 8 registers from 40001 to 40008.
// Therefore, we need at least a 16-byte physical memory.
int RespByteCount; // The total bytes of query data.
```

Finally, make a query. Unlike server programming, the mode is defined as Master instead of Slave.

```c
Modbus_COM_Init(COM1, Master, (unsigned long)9600, NO_PARITY, DATA8, STOP1)
ADAMModbusRTU_Read(COM1, SlaveID, Read_StartAddr, Read_EndAddr, &RespByteCount, Resp_From_Server);
```

Now, the RespByteCount should report this query has get 16 bytes data. But, where is the data? The answer is quite simple as follows: `Resp_From_Server[0] => 40001 Hi byte`  
`Resp_From_Server[1] => 40001 Lo byte`
Example: (Modbus TCP Server and Modbus TCP client)

Assume that we now need a Modbus TCP Server with valid address in the range of 40001-40008. Before starting to create a server, we need to define some server information first such as the total numbers of connections and the timeout setting.

```c
#define TCP_Port 502  //502 is the standard port of modbus protocol
#define iTimeOut 3000  //3000 msec for timeout setting
#define iConns 20      //Only 20 client connections are available
```

And second, we need to allocate a physical memory for address 40001-40008.
```
int ModbusAddr_Mem[8];  //ModbusAddr_Mem[0]=>40001,...,
```

Finally, we can create a server.
```
ADAMTCP_ModServer_Create(TCP_Port, iTimeOut, iConns, (unsigned char*)ModbusAddr_Mem, sizeof(ModbusAddr_Mem));
```

But, how do we put the data to the address 40001-40008 for client queries? Just simply put any data you want to the physical memory.
```
ModbusAddr_Mem[0]=0x1234;  //40001=>0x1234
ModbusAddr_Mem[7]=0x4321;  //40008=>0x4321
```

OK, we've learned the techniques of creating a server. Now, let's see how to make query to get data at 40001-40008 from server. First, define some needed information for querying server.
```
#define Server_Port 502  //502 is the standard port of modbus protocol
#define Server_IP "10.0.0.1" //the IP of server
#define iTimeOut 4000  //4000 msec for timeout setting
#define Read_StartAddr 40001  //query data start from address 40001
#define Read_EndAddr 40008   //query data end to address 40008
#define SlaveID 1
```
Second, we need to allocate a physical memory for query data.

```c
unsigned char Resp_From_Server[16];
// 8 registers from 40001 to 40008. Therefore,
// we need at least a 16-byte physical memory.
int RespByteCount; // The total bytes of query data.
```

And, a descriptor for socket connection is also needed:

```c
SOCKET SO;
```

Finally, make a query.

```c
ADAMTCP_Connect(&SO, Server_IP, Server_Port);
ADAMModbusTCP_Read(&SO, iTimeout, SlaveID, Read_StartAddr,
Read_EndAddr, &RespByteCount, Resp_From_Server);
```

Now, the RespByteCount should report this query has get 16 bytes data. But, where is the data? The answer is quite simple as follows:

- `Resp_From_Server[0]` => 40001 Hi byte
- `Resp_From_Server[1]` => 40001 Lo byte

Above is the concept how to use Modbus protocol, and we also provide examples for reference, please refer the examples under `C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\ModbusAppEx`
Note:
Modbus libraries come from Modbus standard protocol, and every function call can be mapped to a Modbus function. For example, ADAMRTU_ReadCoilStatus function is mapped to Modbus Function code 01 (Read Coil Status). The following is the list of supported Modbus function codes:

<table>
<thead>
<tr>
<th>Modbus Function Codes</th>
<th>Related Modbus Libraries</th>
</tr>
</thead>
<tbody>
<tr>
<td>01 Read Coil Status</td>
<td>ADAMRTU_ReadCoilStatus ADAMTCP_ReadCoilStatus</td>
</tr>
<tr>
<td>02 Read Input Status</td>
<td>ADAMRTU_ReadInputStatus ADAMTCP_ReadInputStatus</td>
</tr>
<tr>
<td>03 Read Holding Registers</td>
<td>ADAMRTU_ReadHoldingRegs ADAMTCP_ReadHoldingRegs</td>
</tr>
<tr>
<td>04 Read Input Registers</td>
<td>ADAMRTU_ReadInputRegs ADAMTCP_ReadInputRegs</td>
</tr>
<tr>
<td>05 Force Single Coil</td>
<td>ADAMRTU_ForceSingleCoil ADAMTCP_ForceSingleCoil</td>
</tr>
<tr>
<td>06 Preset Single Register</td>
<td>ADAMRTU_PresetSingleReg ADAMTCP_PresetSingleReg</td>
</tr>
<tr>
<td>15 Force Multiple Coils</td>
<td>ADAMRTU_ForceMultiCoils ADAMTCP_ForceMultiCoils</td>
</tr>
<tr>
<td>16 Preset Multiple Registers</td>
<td>ADAMRTU_PresetMultiRegs ADAMTCP_PresetMultiRegs</td>
</tr>
</tbody>
</table>

Moreover, we also provide four advanced function calls for beginners.

The Modbus function (01, 02, 03, 04) can be simply integrated into one “read” function as ADAMModbusRTU_Read (for Modbus RTU) or ADAMModbusTCP_Read (for Modbus TCP).

The Modbus function (05, 06, 15, 16) can be simply integrated into one “write” function as ADAMModbusRTU_Write (for Modbus RTU) or ADAMModbusTCP_Write (for Modbus TCP).

However, programmers should notice that those four functions are a little bit slower in performance than the original sixteen functions.

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**Modbus_COM_Init**

**Syntax:**
```c
int Modbus_COM_Init(int Port, int iMode, unsigned long iBaud, int iParity, int iFormat, int iStopBits)
```

**Description:**
Initial a COM port for Modbus/RTU connection.

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Port</td>
<td>COM1</td>
<td>Initial COM1</td>
</tr>
<tr>
<td></td>
<td>COM2</td>
<td>Initial COM2</td>
</tr>
<tr>
<td></td>
<td>COM3</td>
<td>Initial COM3</td>
</tr>
<tr>
<td></td>
<td>COM4</td>
<td>Initial COM4</td>
</tr>
<tr>
<td>iMode</td>
<td>Slave</td>
<td>Modbus/RTU slave mode</td>
</tr>
<tr>
<td></td>
<td>Master</td>
<td>Modbus/RTU master mode</td>
</tr>
<tr>
<td>iBaud</td>
<td>9600, etc ...</td>
<td>The value of baud rate</td>
</tr>
<tr>
<td>iParity</td>
<td>NO_Parity</td>
<td>No parity</td>
</tr>
<tr>
<td></td>
<td>ODD_Parity</td>
<td>Odd parity</td>
</tr>
<tr>
<td></td>
<td>EVEN_Parity</td>
<td>Even parity</td>
</tr>
<tr>
<td></td>
<td>ONE_Parity</td>
<td>Parity=1</td>
</tr>
<tr>
<td></td>
<td>ZERO_Parity</td>
<td>Parity=0</td>
</tr>
<tr>
<td>iFormat</td>
<td>DATA5</td>
<td>5 data bit</td>
</tr>
<tr>
<td></td>
<td>DATA6</td>
<td>6 data bit</td>
</tr>
<tr>
<td></td>
<td>DATA7</td>
<td>7 data bit</td>
</tr>
<tr>
<td></td>
<td>DATA8</td>
<td>8 data bit</td>
</tr>
<tr>
<td>iStopBits</td>
<td>STOP1</td>
<td>One stop bit</td>
</tr>
<tr>
<td></td>
<td>STOP2</td>
<td>Two stop bits</td>
</tr>
</tbody>
</table>

**Return value:**

0   No error occurs.
1   COM_already_installed: COM port has been installed before.
2   Err_Access_COM: Error occurs when try to access COM port.
Example:

```c
if(Modbus_COM_Init(COM2, Master, (unsigned long)9600, NO_PARITY, DATA8, STOP1)!=0)
{
    adv_printf("error\n");
    return;
}
adv_printf("init success!!\n");
```
Modbus_COM_Release

Syntax:
void Modbus_COM_Release(int Port)

Description:
Release the COM port of Modbus connection.

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Port</td>
<td>1</td>
<td>COM1</td>
</tr>
<tr>
<td></td>
<td>2</td>
<td>COM2</td>
</tr>
<tr>
<td></td>
<td>3</td>
<td>COM3</td>
</tr>
<tr>
<td></td>
<td>4</td>
<td>COM4</td>
</tr>
</tbody>
</table>

Return value:
None.
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**Error_Code**

**Syntax:**

```c
int Error_Code(void)
```

**Description:**

When following function call gets error return, this function can get the exact error code for user:
- ADAMRTU_ForceMultiCoils()
- ADAMRTU_ForceSingleCoil()
- ADAMRTU_PresetMultiRegs()
- ADAMRTU_PresetSingleReg()
- ADAMRTU_ReadCoilStatus()
- ADAMRTU_ReadHoldingRegs()
- ADAMRTU_ReadInputRegs()
- ADAMRTU_ReadInputStatus()

**Parameters**

None.

**Return value:**

- NULL No exception error returned.
- Error Code Exception error returned.

**Error code:**

<table>
<thead>
<tr>
<th>Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>91</td>
<td>Invalid Response</td>
</tr>
<tr>
<td>92</td>
<td>COM Port Initial or Mode Error</td>
</tr>
<tr>
<td>93</td>
<td>COM Port Time Out</td>
</tr>
</tbody>
</table>

**Example:**

Refer to `ADAMRTU_ForceMultiCoils`
ADAMRTU_ForceMultiCoils

Syntax:
bool ADAMRTU_ForceMultiCoils(int iPort, int Slave_Addr, int CoilIndex, int TotalPoint, int TotalByte, unsigned char szData[])

Description:
"0F HEX" command of Modbus/RTU function code

Parameters Description
iPort COM port number
Slave_Addr Slave address
CoilIndex Coil address
TotalPoint Quantity of coils
TotalByte Byte count
szData[] Force Data

Return value:
TRUE No error occurs.
FALSE Error occurs, call Error_Code() for exact error codes.

Example:
HostData[0]=0xf0;
if(!ADAMRTU_ForceMultiCoils(COM1, 0x02, 0x64, 0x08, 0x01, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send.\n");
}
else
    adv_printf("Success!!\n");
ADAMRTU_ForceSingleCoil

Syntax:
bool ADAMRTU_ForceSingleCoil(int iPort, int i_iAddr, int i_iCoilIndex, int i_iData)

Description:
"05 HEX" command of Modbus/RTU function code.

Parameters Description
iPort COM port number
i_iAddr Slave address
i_iCoilIndex Coil address
int i_iData Force Data

Return value:
TRUE No error occurs.
FALSE Error occurs, call Error_Code() for exact error codes.

Example:
if(!ADAMRTU_ForceSingleCoil(COM1, 0x02, 0x65, 0))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
}
else
    adv_printf("Success!!");
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**ADAMRTU_PresetMultiRegs**

**Syntax:**
```c
bool ADAMRTU_PresetMultiRegs(int iPort, int i_iAddr, int i_iStartReg,
int i_iTotalReg, int i_iTotalByte, unsigned char i_szData[])
```

**Description:**
“10 HEX” command of Modbus RTU function code

**Parameters**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>iPort</td>
<td>COM port number</td>
</tr>
<tr>
<td>i_iAddr</td>
<td>Slave address</td>
</tr>
<tr>
<td>i_iStartReg</td>
<td>Starting Address</td>
</tr>
<tr>
<td>i_iTotalReg</td>
<td>No. of Registers Hi</td>
</tr>
<tr>
<td>i_iTotalByte</td>
<td>Byte Count</td>
</tr>
<tr>
<td>i_szData[]</td>
<td>Data</td>
</tr>
</tbody>
</table>

**Return value:**

<table>
<thead>
<tr>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>TRUE</td>
<td>No error occurs.</td>
</tr>
<tr>
<td>FALSE</td>
<td>Error occurs, call <code>Error_Code()</code> for exact error codes.</td>
</tr>
</tbody>
</table>

**Example:**

```c
HostData[0]=0x12;
HostData[1]=0x56;
HostData[2]=0x38;
HostData[3]=0x09;

if(!ADAMRTU_PresetMultiRegs(COM1, 0x02, 0x64, 2, 4, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
    return;
}
else
    adv_printf("Success!!");
```
ADAMRTU_PresetSingleReg

Syntax:
bool ADAMRTU_PresetSingleReg(int iPort, int i_iAddr, int i_iRegIndex, int i_iData)

Description:
“06 HEX” command of Modbus RTU function code

Parameters Description
iPort COM port number
i_iAddr Slave Address
i_iRegIndex Register Address
i_iData Preset Data

Return value:
TRUE No error occurs.
FALSE Error occurs, call Error_Code() for exact error codes.

Example:
if(!ADAMRTU_PresetSingleReg(COM1, 0x02, 0x68, 0x1234))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
    return;
}
else
    adv_printf("Success!!");
### ADAMModbusRTU_Write

**Syntax:**
```c
bool ADAMModbusTCP_Write(SOCKET * SO, int WaitMilliSec, int Slave_Addr, unsigned long i_iStartAddr, unsigned long i_iEndAddr, unsigned char i_szData[]);
```

**Description:**
Presets values or forces coils into a sequence of holding registers (4X references) or a sequence of coilds(0X references).

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>iPort</td>
<td>COM port number</td>
</tr>
<tr>
<td>Slave_Addr</td>
<td>Address ID of slave device (valid slave device addresses id are in the range of 0-247 decimal)</td>
</tr>
<tr>
<td>i_iStartAddr</td>
<td>The start address of slave device</td>
</tr>
<tr>
<td>i_iEndAddr</td>
<td>The end address of slave device</td>
</tr>
<tr>
<td>i_szData</td>
<td>The buffer of query data contents</td>
</tr>
</tbody>
</table>

**Return value:**
ADAMModbusRTU_Write() returns TRUE if it is successful. On an error, a value of FALSE will be return and the function Error_Code() can be used to get the last error.

**Example:**

please refer the examples under
C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\ModbusAppEx
ADAMRTU_ReadCoilStatus

Syntax:
bool ADAMRTU_ReadCoilStatus(int iPort, int i_iAddr, int i_iStartIndex,
int i_iTotalPoint, int *o_iTotalByte, unsigned char o_szData[])

Description:
"01HEX" command of Modbus RTU function code.

Parameters Description
iPort COM port number
i_iAddr Slave Address
i_iStartIndex Starting Address
i_iTotalPoint No. of Points
o_iTotalByte Byte Count
o_szData[] Coil Data

Return value:
TRUE No error occurs.
FALSE Error occurs, call Error_Code() for exact error codes.

Example:
if(!ADAMRTU_ReadCoilStatus(COM1, 0x02, 0x6E, 0x01,
&DataByteCount, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
}
else
{
    adv_printf("Status: ");
    for(tmpcnt=0; tmpcnt<DataByteCount; tmpcnt++)
    {
        adv_printf("%02X", HostData[tmpcnt]);
    }
    adv_printf("\n");
}
ADAMRTU_ReadHoldingRegs

Syntax:

```c
bool ADAMRTU_ReadHoldingRegs(int iPort, int i_iAddr, int i_iStartIndex, int i_iTotalPoint, int *o_iTotalByte, unsigned char o_szData[])
```

Description:

“03 HEX” command of Modbus RTU function code.

Parameters Description

- `iPort` COM port number
- `i_iAddr` Slave Address
- `i_iStartIndex` Starting Address
- `i_iTotalPoint` No. of Points
- `o_iTotalByte` Byte Count
- `o_szData[]` Register Data

Return value:

- TRUE No error occurs.
- FALSE Error occurs, call `Error_Code()` for exact error codes.

Example:

```c
if(!ADAMRTU_ReadHoldingRegs(COM1, 0x02, 0x65, 0x01, &DataByteCount, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..\n");
}
else
{
    adv_printf("Status: ");
    for(tmpcnt=0; tmpcnt<DataByteCount; tmpcnt++)
    {
        adv_printf("%02X", HostData[tmpcnt]);
    }
    adv_printf("\n");
}
```
ADAMRTU_ReadInputRegs

Syntax:
```c
bool ADAMRTU_ReadInputRegs(int iPort, int i_iAddr, int i_iStartIndex,
int i_iTotalPoint, int *o_iTotalByte, unsigned char o_szData[])
```

Description:
"04 HEX" command of Modbus RTU function code.

Parameters Description
- **iPort**: COM port number
- **i_iAddr**: Slave Address
- **i_iStartIndex**: Starting Address
- **i_iTotalPoint**: No. of Points
- **o_iTotalByte**: Byte Count
- **o_szData[]**: Register Data

Return value:
- **TRUE**: No error occurs.
- **FALSE**: Error occurs, call `Error_Code()` for exact error codes.

Example:
```c
if(!ADAMRTU_ReadInputRegs(COM1, 0x02, 0x65, 0x01,
&DataByteCount, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
}
else
{
    adv_printf("Status: ");
    for(tmpcnt=0; tmpcnt<DataByteCount; tmpcnt++)
    {
        adv_printf("%02X", HostData[tmpcnt]);
    }
    adv_printf("\n");
}
```
Chapter 5 Programming and Function Library

ADAMRTU_ReadInputStatus

Syntax:
```cpp
bool ADAMRTU_ReadInputStatus(int iPort, int i_iAddr, int i_iStartIndex, int i_iTotalPoint, int *o_iTotalByte, unsigned char o_szData[])
```

Description:
“02 HEX” command of Modbus RTU function code.

Parameters Description

- **iPort**: COM port number
- **i_iAddr**: Slave Address
- **i_iStartIndex**: Starting Address
- **i_iTotalPoint**: No. of Points
- **o_iTotalByte**: Byte Count
- **o_szData[]**: Inputs Data

Return value:
- **TRUE**: No error occurs.
- **FALSE**: Error occurs, call `Error_Code()` for exact error codes.

Example:
```cpp
if(!ADAMRTU_ReadInputStatus(COM1, 0x02, 0x64, 0x08, &DataByteCount, HostData))
{
    adv_printf("err code is %d\n", Error_Code());
    adv_printf("fail send..");
}
else
{
    adv_printf("Status: ");
    for(tmpcnt=0; tmpcnt<DataByteCount; tmpcnt++)
    {
        adv_printf("%02X", HostData[tmpcnt]);
    }
    adv_printf("\n");
}
```
ADAMModbusRTU_Read

Syntax:
`bool ADAMModbusRTU_Read(int iPort, int Slave_Addr, unsigned long i_iStartAddr, unsigned long i_iEndAddr, unsigned int *o_iByteOfResp, unsigned char o_szResp[]);`

Description:
Reads the On/OFF status of 0X/1X references (coils) or the binary contents of 3X/4X references (registers) in the slave.

Parameters Description
---
iPort | COM port number
Slave_Addr | Address ID of slave device (valid slave device addresses id are in the range of 0-247 decimal)
i_iStartAddr | The start address of slave device
i_iEndAddr | The end address of slave device
i_iTotalPoint | The total number of coils/regs to be read
o_iByteOfResp | The total bytes of the response data contents
o_szResp | The buffer of response data contents

Return value:
ADAMModbusRTU_Read() returns TRUE if it is successful. On an error, a value of FALSE will be return and the function Error_Code() can be used to get the last error.

Example:
please refer the examples under
`C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\ModbusAppEx`
Chapter 5 Programming and Function Library

**ADAMRTU_ModServer_Create**

**Syntax:**

```c
void ADAMRTU_ModServer_Create(int slave_addr, unsigned char *ptr_mem, unsigned int size_of_mem)
```

**Description:**

Create Modbus/RTU Server function.

**Parameters Description**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>slave_addr</td>
<td>Slave address of Modbus/RTU Server</td>
</tr>
<tr>
<td>ptr_mem</td>
<td>Share memory</td>
</tr>
<tr>
<td>size_of_mem</td>
<td>Size of share memory</td>
</tr>
</tbody>
</table>

**Return value:**

None.

**Example:**

```
ADAMRTU_ModServer_Create(3, (unsigned char *)Share_Mem, sizeof(Share_Mem));

    adv_printf("server started..\n");

    while(1)
    {
        if(predate != Share_Mem[0])
        {
            adv_printf("40001 is %X\n", Share_Mem[0]);
            //strongly recommend use adv_printf() instead of printf()
            predate = Share_Mem[0];
        }
    }
```
Chapter 5 Programming and Function Library

Ver_RTU_Mod

Syntax:
void Ver_RTU_Mod(char *vstr)

Description:
Check Modbus/RTU Library version.

Parameter Description
vstr Pointer to array of Modbus/RTU Library version information

Return value:
None.

Example:

char library_ver[20];

void main(void)
{
    Ver_RTU_Mod(library_ver);
    adv_printf("The version of library is %s\n", library_ver);
}

5.3.5 MODBUS/TCP Functions (MBTCP*.LIB)

**Ver_TCP_Mod**

**Syntax:**
void Ver_TCP_Mod(char *vstr)

**Description:**
Check Modbus/TCP Library version.

**Parameter Description**
- vstr Pointer   to   array   of   Modbus/TCP   Library version information.

**Return value:**
None.

**Example:**

```c
char library_ver[20];

void main(void)
{
    Ver_TCP_Mod(library_ver);
    adv_printf("The version of library is %s\n", library_ver);
}
```
Modbus TCP Client Functions:

ReturnErr_code

Syntax:
int ReturnErr_code(void)

Description:
When following function call gets error return, this function can get the exact error code for user.

ADAMTCP_ForceMultiCoils()
ADAMTCP_ForceSingleCoil()
ADAMTCP_PresetMultiRegs()
ADAMTCP_PresetSingleReg()
ADAMTCP_ReadCoilStatus()
ADAMTCP_ReadHoldingRegs()
ADAMTCP_ReadInputRegs()
ADAMTCP_ReadInputStatus()

Parameters
None.

Return value:
NULL No error occurs.
Erro Code Exception error returned.

Error code:
01 ILLEGAL FUNCTION
02 ILLEGAL DATA ADDRESS
03 ILLEGAL DATA VALUE
04 SLAVE DEVICE FAILURE
05 ACKNOWLEDGE
06 SLAVE DEVICE BUSY
07 NEGATIVE ACKNOWLEDGE
08 MEMORY PARITY ERROR
Chapter 5 Programming and Function Library

Example:

```c
SOCKET SO_4500;
...

if(ADAMTCP_ReadCoilStatus(&SO_4500, 50, 0x01, 0x10, 0x11, &DataByteCount, HostData)<=0)
{
   perror("ADAMTCP_ReadCoilStatus()\n");
   adv_printf("err code is %d\n", ReturnErr_code());
   ADAMTCP_Disconnect(&SO_4500);
   return 0;
}
```
ADAMTCP_Connect

Syntax:
int ADAMTCP_Connect(SOCKET * SO, char * Target_IP, int Target_Port)

Description:
Connect to Modbus/TCP Server.

Parameters Description
SO A descriptor identifying an unconnected socket.
Target_IP Modbus/TCP server IP.
Target_Port Server port for the connection.

Return value:
TRUE No error occurs
-1 Error occurs when gets the host name
-2 The socket is invalid when initializes the socket
-3 Error occurs when connects to Modbus/TCP server

Example:
if(ADAMTCP_Connect(&SO_4500, ServerIP, Server_Port)<=0)
{
    perror("ADAMTCP_Connect()");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
Chapter 5 Programming and Function Library

ADAMTCP_Disconnect

Syntax:
bool ADAMTCP_Disconnect(SOCKET * SO)

Description:
Disconnect to Modbus/TCP Server.

Parameters
SO A descriptor identifying the connected socket to Modbus/TCP server.

Return value:
TRUE No error occurs
FALSE There is error occurs

Example:
if(ADAMTCP_Connect(&SO_4500, ServerIP, Server_Port)<=0)
{
    perror("ADAMTCP_Connect()");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}

ADAMTCP_ForceMultiCoils

Syntax:
int  ADAMTCP_ForceMultiCoils(SOCKET  *  SO,  int  WaitMilliSec,
int Slave_Addr, int CoiIndex, int TotalPoint, int TotalByte, unsigned char szData[])

Description:
"0F HEX" command of Modbus TCP function code.

Parameters Description
SO                  The socket connected to Modbus/TCP server
WaitMilliSec       Set duration (msec unit) for the response from
                   Modbus/TCP server
Slave_Addr         Slave address
CoilIndex           Coil address
TotalPoint          Quantity of coils
TotalByte           Byte count
szData[]            Force Data

Return value:
TRUE               No error occurs
0                   Time out error when receive modbus query message from Modbus/TCP server
-1                  Error occurs when send modbus query message to Modbus/TCP server
-2                  Error occurs when receive modbus query message from Modbus/TCP server

Example:
HostData[1]=~0x33;
//force channel status to 0x3333
if(ADAMTCP_ForceMultiCoils(&SO_4500, 50, 0x01, 0x21, 0x10, 0x02,
HostData)<=0) {
    perror("ADAMTCP_ForceMultiCoils()\n");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
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ADAMTCP_ForceSingleCoil

Syntax:
int ADAMTCP_ForceSingleCoil(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int CoilIndex, int Data)

Description:
“05 HEX” command of Modbus TCP function code.

Parameters | Description
---|---
SO | The socket connected to Modbus/TCP server
WaitMilliSec | Set duration (msec unit) for the response from Modbus/TCP server
Slave_Addr | Slave address
CoilIndex | Coil address
Data | Force Data

Return value:
TRUE | No error occurs
0 | Time out error when receive modbus query message from Modbus/TCP server
-1 | Error occurs when send modbus query message to Modbus/TCP server
-2 | Error occurs when receive modbus query message from Modbus/TCP server

Example:
if(ADAMTCP_ForceSingleCoil(&SO_4500, 50, 0x01, 0x25, 1)<=0)
{
    perror("ADAMTCP_ForceSingleCoil()");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
ADAMTCP_PresetMultiRegs

Syntax:
int ADAMTCP_PresetMultiRegs(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int StartReg, int TotalReg, int TotalByte, unsigned char Data[])

Description:
“10 HEX” command of Modbus TCP function code.

Parameters Description
SO The socket connected to Modbus/TCP server
WaitMilliSec Set duration (msec unit) for the response from Modbus/TCP server
Slave_Addr Slave address
StartReg Starting address
TotalReg No. of registers
TotalByte Byte count
szData[] Data

Return value:
TRUE No error occurs
0 Time out error when receive modbus query message from Modbus/TCP server
-1 Error occurs when send modbus query message to Modbus/TCP server
-2 Error occurs when receive modbus query message from Modbus/TCP server

Example:
HostData[0]=0x07;
HostData[1]=0x00;
HostData[2]=0x07;
HostData[3]=0x00;

if(ADAMTCP_PresetMultiRegs(&SO_4500, 50, 0x01, 0x19, 0x02, 4, HostData)<=0)
{
    perror("ADAMTCP_PresetMultiRegs()\n");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;

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Chapter 5 Programming and Function Library

}
**ADAMTCP_PresetSingleReg**

**Syntax:**
```c
int ADAMTCP_PresetSingleReg(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int RegIndex, int Data)
```

**Description:**
“06 HEX” command Modbus TCP function code.

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO</td>
<td>The socket connected to Modbus/TCP server</td>
</tr>
<tr>
<td>WaitMilliSec</td>
<td>Set duration (msec unit) for the response from</td>
</tr>
<tr>
<td>Slave_Addr</td>
<td>Slave address</td>
</tr>
<tr>
<td>RegIndex</td>
<td>Register address</td>
</tr>
<tr>
<td>Data</td>
<td>Preset Data</td>
</tr>
</tbody>
</table>

**Return value:**
- TRUE: No error occurs
- 0: Time out error when receive modbus query message from Modbus/TCP server
- -1: Error occurs when send modbus query message to Modbus/TCP server
- -2: Error occurs when receive modbus query message from Modbus/TCP server

**Example:**
```c
if(ADAMTCP_PresetSingleReg(&SO_4500, 50, 0x01, 0x19, 0x07ff)<=0)
{
    perror("ADAMTCP_PresetSingleReg()\n");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
```
Chapter 5 Programming and Function Library

ADAMModbusTCP_Write

Syntax:
bool ADAMModbusTCP_Write(SOCKET * SO, int WaitMillisec, int Slave_Addr, unsigned long i_iStartAddr, unsigned long i_iEndAddr, unsigned char i_szData[]);

Description:
Presets values or forces coils into a sequence of holding registers (4X references) or a sequence of coils(0X references).

Parameters Description
SO The socket connected to Modbus/TCP server
WaitMillisec The maximum time of ADAMModbusTCP_Write()
Slave_Addr Address ID of slave device (valid slave device addresses id are in the range of 0-247 decimal)
i_iStartAddr The start address of slave device
i_iEndAddr The end address of slave device
i_szData The buffer of query data contents

Return value:
ADAMModbusTCP_Write() returns TRUE if it is successful. On an error, a value of FALSE will be return and the function Error_Code() can be used to get the last error.

Example:
please refer the examples under
C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\ModbusAppEx
ADAMTCP_ReadCoilStatus

Syntax:

```c
int ADAMTCP_ReadCoilStatus(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int StartIndex, int TotalPoint, int * ByteCount, char * wData)
```

Description:

"01 HEX" command of Modbus TCP function code

Parameter Description

- **SO**: The socket connected to Modbus/TCP server
- **WaitMilliSec**: Set duration (msec) for the response from Modbus/TCP server
- **Slave_Addr**: Slave address
- **StartIndex**: Starting address
- **TotalPoint**: No. of points
- **ByteCount**: Byte count
- **wData**: Data

Return value:

- **TRUE**: No error occurs
- **0**: Time out error when receive modbus query message from Modbus/TCP server
- **-1**: Error occurs when send modbus query message to Modbus/TCP server
- **-2**: Error occurs when receive modbus query message from Modbus/TCP server

Example:

```c
if(ADAMTCP_ReadCoilStatus(&SO_4500, 50, 0x01, 0x11, 0x10, &DataByteCount, HostData)<=0)
{
    perror("ADAMTCP_ReadCoilStatus()\n");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
else
{
    adv_printf("Adam-4500 Status: ");
    for(tmp=0; tmp<DataByteCount; tmp++)
    {
        adv_printf("%2X", HostData[tmp]);
    }
}
```

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adv_printf("\n");
}
ADAMTCP_ReadHoldingRegs

Syntax:
int ADAMTCP_ReadHoldingRegs(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int StartIndex, int TotalPoint, int * ByteCount, char wData)

Description:
"03 HEX" command of Modbus TCP function code.

Parameters Description
SO The socket connected to Modbus/TCP server
WaitMilliSec Set duration(msec unit) for the response from Modbus/TCP server
Slave_Addr Slave address
StartIndex Starting address
TotalPoint No. of points
ByteCount Byte count
wData Data

Return value:
TRUE No error occurs
0 Time out error when receive modbus query message from Modbus/TCP server
-1 Error occurs when send modbus query message to Modbus/TCP server
-2 Error occurs when receive modbus query message from Modbus/TCP server

Example:
//This example demonstrates how to use ADAMTCP_ReadHoldingRegs() to query remote Modbus TCP module, such as ADAM-5000/TCP. And it queries all channels of ADAM-5024 inserted in Slot 3 on the ADAM-5000/TCP.

if((errno=ADAMTCP_ReadHoldingRegs(&SO_4500, 50, 0x01, 0x19, 0x08, &DataByteCount, HostData))<=0)
{
perror("ADAMTCP_ReadHoldingRegs()\n");
adv_printf("errno is %d\n", errno);
}
Chapter 5 Programming and Function Library

ADAMTCP_Disconnect(&SO_4500);
return 0;

}
else
{
  adv_printf("Adam-5024 Status: ");
  for(tmp=0; tmp<DataByteCount; tmp++)
  {
    adv_printf("%02X", HostData[tmp]);
  }
  adv_printf("\n");
}
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ADAMTCP_ReadInputRegs

Syntax:
```c
int ADAMTCP_ReadInputRegs(SOCKET * SO, int WaitMilliSec,
Slave_Addr, int StartIndex, int TotalPoint, int * ByteCount,
char * wData)
```

Description:
“04 HEX” command of Modbus TCP function code.

Parameter Description
- **SO**: The socket connected to Modbus/TCP server
- **WaitMilliSec**: Set duration (msec unit) for the response from Modbus/TCP server
- **Slave_Addr**: Slave address
- **StartIndex**: Starting address
- **TotalPoint**: No. of points
- **ByteCount**: Byte count
- **wData**: Data

Return value:
- **TRUE**: No error occurs
- **0**: Time out error when receive modbus query message from Modbus/TCP server
- **-1**: Error occurs when send modbus query message to Modbus/TCP server
- **-2**: Error occurs when receive modbus query message from Modbus/TCP server

Example:
```
//This example demonstrates how to use ADAMTCP_ReadInputRegs
to query remote Modbus TCP module, such as ADAM-5000/TCP. And here it queries all chanels of ADAM-5024 inserted in Slot 3 on the ADAM-5000/TCP.

if((errno=ADAMTCP_ReadInputRegs(&SO_4500, 50, 0x01, 0x19,
0x08, &DataByteCount, HostData))<=0)
{
perror("ADAMTCP_ReadInputRegs()\n");
adv_printf("errno is %d\n", errno);
```

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ADAMTCP_Disconnect(&SO_4500);
return 0;
}

else
{
    adv_printf("Adam-5024 Status: ");
    for(tmp=0; tmp<DataByteCount; tmp++)
    {
        adv_printf("%02X", HostData[tmp]);
    }
    adv_printf("\n");
}
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ADAMTCP_ReadInputStatus

Syntax:
int ADAMTCP_ReadInputStatus(SOCKET * SO, int WaitMilliSec, int Slave_Addr, int StartIndex, int TotalPoint, int * ByteCount, char *wData)

Description:
“02 HEX” command Modbus TCP function code.

Parameters | Description
--- | ---
SO | The socket connected to Modbus/TCP server
WaitMilliSec | Set duration (msec unit) for the response from Modbus/TCP server
Slave_Addr | Slave address
StartIndex | Starting address
TotalPoint | No. of points
ByteCount | Byte count
wData | Data

Return value:
TRUE | No error occurs
0 | Time out error when receive modbus query message from Modbus/TCP server
-1 | Error occurs when send modbus query message to Modbus/TCP server
-2 | Error occurs when receive modbus query message from Modbus/TCP server

Example:

```c
//This example demonstrates how to use ADAMTCP_ReadInputStatus to query remote Modbus TCP module, such as ADAM-5000/TCP. And here it queries ADAM-5051 inserted in Slot 1 on the ADAM-5000/TCP.

if(ADAMTCP_ReadInputStatus(&SO_4500, 50, 0x01, 0x11, 0x10, &DataByteCount, HostData)<=0)
{
    perror("ADAMTCP_ReadInputStatus()");
    ADAMTCP_Disconnect(&SO_4500);
    return 0;
}
```
else
{
    adv_printf("Adam-5051 Status: ");
    for(tmp=0; tmp<DataByteCount; tmp++)
    {
        adv_printf("%2X", HostData[tmp]);
    }
    adv_printf("\n");
}
ADAMModbusTCP_Read

Syntax:

```c
bool ADAMModbusTCP_Read(SOCKET * SO, int WaitMilliSec, int Slave_Addr, unsigned long i_iStartAddr, unsigned long i_iEndAddr, unsigned int *o_iByteOfResp, unsigned char o_szResp[]);
```

Description:
Reads the On/OFF status of 0X/1X references (coils) or the binary contents of 3X/4X references (registers) in the slave.

Parameters Description
- **SO**: The socket connected to Modbus/TCP server
- **WaitMilliSec**: The maximum time of ADAMModbusTCP_Read()
- **Slave_Addr**: Address ID of slave device (valid slave device addresses id are in the range of 0-247 decimal)
- **i_iStartAddr**: The start address of slave device
- **i_iEndAddr**: The end address of slave device
- **i_iTotalPoint**: The total number of coils/regs to be read
- **o_iByteOfResp**: The total bytes of the response data contents
- **o_szResp**: The buffer of response data contents

Return value:
ADAMModbusRTU_Read() returns TRUE if it is successful. On an error, a value of FALSE will be return and the function Error_Code() can be used to get the last error.

Example:
please refer the examples under
C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Example\ModbusAppEx.
Modbus TCP Server Functions:

ADAMTCP_ModServer_Create

Syntax:
int  ADAMTCP_ModServer_Create(int Host_Port, unsigned long waittimeout, unsigned int numberConns, unsigned char * ptr_mem, int size_mem)

Description:
Create a Modbus/TCP Server.

Parameters Description
Host_Port The port for Modbus/TCP server
Waittimeout Time out value, 0~0xffffffff milli-second
NumberConns Maximum connections for client
ptr_mem Share memory
size_mem The size of share memory

Return value:
0 No error occurs
91 Invalid socket
92 Error occurs when associates a local socket address with a socket
93 Error occurs when sets up the socket mode
94 Error occurs when listens to the incoming socket

Example:
if((err_code=ADAMTCP_ModServer_Create(502, 5000, 20, (unsigned char *)Share_Mem, sizeof(Share_Mem)))!=0)
{
    adv_printf("error code is %d/n", err_code);
}
adv_printf("Server started, wait for connect...\n");
ADAMTCP_ModServer_Update

Syntax:
int ADAMTCP_ModServer_Update(void)

Description:
Update the Modbus/TCP Server. The Modbus/TCP server needs to be updated by calling ADAMTCP_ModServer_Update() function continuously to keep server alive.

Parameters
None.

Return value:
1  New message has come in
0  No new message comes in

Example:
while(1) {
    iState = ADAMTCP_ModServer_Update();  //second step
    if(iState) { //if has message, show the data at address 40001
        if(pre_data != Share_Mem[0]) {
            adv_printf("40001 is %X\n", Share_Mem[0]);
            //notice: printf() will decrease server performance
            pre_data = Share_Mem[0];
        }
    }
}
ADAMTCP_ModServer_Release

Syntax:
void ADAMTCP_ModServer_Release(void)

Description:
Release Modbus/TCP Server.

Parameters
None.

Returned value:
None.
5.4.6 Socket Functions (SOCKET*.LIB)

TCP/IP SOCKETS API Overview

This section describes the SOCKETS API, which is compatible with the BSD Sockets API and also the Winsock API. The definitions and prototypes for the C environment are supplied in SOCKET.H, while the implementation of the C interface is in SOCKET.C. The SOCKETS API is implemented as a layer on top of the Compatible API (CAPI) and provides an interface to the socket and name resolution facilities provided by the Datalight DOS SOCKETS product. It also provides the database functions of BSD Sockets and Winsock.

A socket is an end-point for a connection and is defined by the combination of a host address (also known as an IP address), a port number (or communicating process ID), and a transport protocol, such as UDP or TCP. Two connected SOCKETS using the same transport protocol define a connection. The API uses a socket handle, sometimes referred to as simply a socket. The socket handle is required by most function calls in order to access a connection. The socket handle used is the same as a normal socket as used in CAPI.

A socket handle is obtained by calling the `socket()` function. A socket handle can only be used for a single connection. When no longer required, such as when a connection has been closed, the socket handle must be released by calling `closesocket()`. Socket handles are positive numbers greater than 63.

Types of Service

SOCKETS can be used with one of two service types:

- SOCK_STREAM (using TCP).
- SOCK_DGRAM (using UDP).

A stream connection provides for the bi-directional, reliable, sequenced, and unduplicated flow of data without record boundaries. No broadcast facilities can be used with a stream connection.

A datagram connection supports bi-directional flow of data that is not guaranteed to be sequenced, reliable, or unduplicated. That is, a process receiving messages on a datagram socket may find messages duplicated, and,
possibly, in an order different from the order in which it was sent. An important characteristic of a datagram connection is that record boundaries in data are preserved.
Datagram connections closely model the facilities found in many contemporary packet switched networks such as Ethernet. Broadcast messages may be sent and received.

Establishing Remote Connections

To establish a connection, one side (the server) must execute a `listen()` and and subsequent `accept()` and the other side (the client) a `connect()`. A connection consists of the local socket / remote socket pair. It is therefore possible to have a connection within a single host as long as the local and remote port values differ. Each host in an IP network must have at least one host address also known as an IP address. When a host has more than one physical connection to an IP network, it may have more than one IP address. An IP address must be unique within a network. An IP address is 32 bits in length, a port number 16 bits. A value of zero means “any” while a binary value of all 1s means “all.” The latter value is used for broadcasting purposes. Using the `sockaddr` structure conveys the addresses (host/port) to be used in a connection. A local association is performed by the `bind()` function.

Using SOCK_STREAM and SOCK_DGRAM Services

When using the SOCK_STREAM service (TCP), bi-directional data can be sent using the `send()` or `sendto()` functions and received using the `recv()` or `recvfrom()` functions until one side performs a `shutdown(1)` or `shutdown(2)` after which that side cannot send any more data, but can still receive data until the other side performs a `shutdown(1)`, `shutdown(2)` or `closesocket()`.

When using the SOCK_DGRAM service, datagrams can be sent without first establishing a “connection”. In fact UDP provides a “connectionless” service although the connection paradigm is used.

Blocking and Non-blocking Operations

The default behavior of socket functions is to block on an operation and only return when the operation has completed. For example, the `connect()` function only returns after the connection has been performed or an error is encountered. This behavior applies to most socket function calls, such as `recv()` and even `send()`, and especially on SOCK_STREAM connections.
In many, if not most applications, this behavior is unacceptable in the single-threaded DOS environment and must be modified. This modification can be accomplished by making all operations on a socket non-blocking by calling `ioctlsocket()` with the FIONBIO option. If a non-blocking operation is performed, the function always returns immediately. If the function could not complete without blocking, an error is returned with `errno` containing EWOULDBLOCK. This error should be regarded as a recoverable error and the operation should be retried, preferably at some later time.

**Out of band data**

TCP “out of band” or urgent data is not implemented. Setting the MSG_OOB flag has no effect in `recv()`, `recvfrom()`, `send()` or `sendto()`; it will simply be ignored. The SO_OOBINLINE option will also be ignored and `ioctlsocket()` with the SIOCATMARK command, will always return an argument value of 1.

**Error Reporting**

In general, the C functions implementing the SOCKETS API return a value of SOCKET_ERROR if the return type is `int` and an error is encountered, in which case, the actual error code is returned in a common variable `errno`. ERR_RE_ENTRY is returned when the SOCKETS kernel has been interrupted. This condition can occur only when the API is called from an interrupt service routine. Programs designed for this type of operation, such as TSR programs activated by a real time clock interrupt, should be coded to handle this error by re-trying the function at a later stage.

**Other sources of Information**

Many good books have been written on the Sockets API:

Pocket Guide to TCP/IP Sockets (C Version) by Michael J. Donahoo, Kenneth L. Calvert

Windows Sockets Network Programming (Addison-Wesley Advanced Windows Series) by Bob Quinn, et al; Hardcover

Internetworking with TCP/IP Vol. III Client-Server Programming
Chapter 5 Programming and Function Library
and Applications-Windows Sockets Version by Douglas E. Comer,
David L. Stevens (Contributor); Hardcover.

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Chapter 5 Programming and Function Library

The Winsock 1.1 help file (WINSOCK.HLP) is also a very useful source of information.

Porting Issues

When porting an application from another BSD Sockets environment like Unix, Linux or Windows (Winsock), a number of issues must be kept in mind. The most important one is that ROM-DOS is a single-user, single-task, single-thread operating system. The use of blocking calls will suspend the system until completion, which may imply an indefinite time under abnormal or even normal conditions. In addition no completion event such as a WSAAsyncSelect windows message for Winsock or a Signal for Unix/Linux is available. Only applications either using nonblocking operations or the select() function may be ported successfully. Other applications must be adapted to follow these guidelines.

Unlike Winsock and like BSD Sockets, an error number is returned in the errno variable and is only valid directly after an API call. When writing portable code to run on both SAPI and Winsock, a simple #define can normally be used i.e.

```c
#ifdef _Windows
#define Errno WSAGetLastError()
#else
#define Errno errno
#endif
```

```c
if (Errno == WSAEWOULDBLOCK)
{
    ...
}
```

Like in Winsock both the WSAE... of Winsock and the E... error definitions of BSD may be used e.g. WSAEWOULDBLOCK and EWOULDBLOCK. The actual error numbers are the same as that of Winsock, except in cases of DOS error code conflicts e.g. WSAEINVAL has the same value as the DOS EINVAL. Always using the symbolic value and not numeric values, will avoid potential
problems.
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The function gethostbyaddr() will always fail with errno == WSANO_DATA.

All the file/socket operations of BSD Sockets must be translated to the *socket() versions as used in Winsock e.g. closesocket() instead of just close().

In Linux/Unix a socket descriptor can be treated the same as a file descriptor; not so for SAPI or Winsock.

For Winsock the WSAStartup() and WSACleanup() functions must be called; make it conditional for portable code.

The "socket set" is defined differently for SAPI/Winsock on the one hand and LINUX/UNIX on the other. Always use the FD_* macros for portable code.

Function Reference

The following sections describe the individual functions of the SOCKETS API.
accept

Syntax:
SOCKET accept ( SOCKET so, struct sockaddr *psAddress, int *piAddressLen )

Description:
Accepts a connection on a socket.

Parameters
so A descriptor identifying a socket which is listening for connections after a listen().
psAddress An optional pointer to a buffer which receives the socket address of the connecting peer.
piAddrLen An optional pointer to an integer which contains the length of the address psAddress.

Return Value
If no error occurs, accept() returns a value of type SOCKET which is a descriptor for the accepted packet. Otherwise, a value of INVALID_SOCKET is returned, and a specific error code is returned in errno.

The integer referred to by piAddressLen initially contains the amount of space pointed to by psAddress. On return it will contain the actual length in bytes of the socket address returned.

Error Codes
ENETDOWN The network subsystem has failed.
EFAULT The *piAddressLen argument is small (less than the sizeof a struct sockaddr).
EINVAL listen() was not invoked prior to accept().
EMFILE The queue is empty upon entry to accept() and there are no descriptors available.
ENOBUFS No buffer space is available.
ENOTSOCK The descriptor is not a socket.
EOPNOTSUPP The referenced socket is not a type that supports connection-oriented service.
EWOULDBLOCK The socket is marked as non-blocking and no connections are present to be accepted.
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Remarks
This function extracts the first connection on the queue of pending connections on listening socket so, creates a new socket with the same properties as so and returns a handle to the new socket. If no pending connections are present on the queue, and the socket is not marked as non-blocking, accept() blocks the caller until a connection is present. If the socket is marked non-blocking and no pending connections are present on the queue, accept() returns an error as described below. Socket so remains listening.

The argument psAddress is a result parameter that is filled in with the socket address of the connecting peer. The piAddressLen is a value-result parameter; it should initially contain the amount of space pointed to by psAddress; on return it will contain the actual length (in bytes) of the socket address returned. This call is used with the connection-based SOCK_STREAM socket type. If psAddress and/or piAddressLen are equal to NULL, then no information about the remote peer socket address of the accepted socket is returned.

See Also
bind(), connect(), listen(), select(), socket()
bind

Syntax: 
```c
int bind ( SOCKET so, const struct sockaddr * psAddress, int iAddressLen )
```

Description: 
Associates a local socket address with a socket.

Parameters
- **so**: A descriptor identifying an unbound socket.
- **psAddress**: The socket address to assign to the socket.
  The sockaddr structure is defined as follows:
  ```c
  struct sockaddr
  {
    u_short sa_family;
    char sa_data[14];
  };
  ``
- **iAddressLen**: The length of the name **psAddress**.

Return Value
If no error occurs, **bind()** returns 0. Otherwise, it returns SOCKET_ERROR, and a specific error code is returned in **errno**.

Error Codes
- **ENETDOWN**: SOCKETS has detected that the network subsystem has failed.
- **EADDRINUSE**: The specified address is already in use. (See the SO_REUSEADDR socket option under setsockopt().)
- **EFAULT**: The **iAddressLen** argument is too small (less than the size of a struct sockaddr).
- **EAFNOSUPPORT**: The specified address family is not supported by this protocol.
- **EINVAL**: The socket is already bound to an address.
- **ENOBUFS**: Not enough buffers available, too many connections.
- **ENOTSOCK**: The descriptor is not a socket.
Remarks
This routine is used on an unconnected datagram or stream socket, before subsequent connect()s or listen()s. When a socket is created with socket(), it exists in a name space (address family), but it has no socket address assigned. bind() establishes the local association (host address/port number) of the socket by assigning a local address to an unnamed socket.

In the Internet address family, an address consists of several components. For SOCK_DGRAM and SOCK_STREAM, the address consists of three parts: a host address, the protocol number (set implicitly to UDP or TCP, respectively), and a port number which identifies the application. If an application does not care what address is assigned to it, it may specify an Internet address equal to INADDR_ANY, a port equal to 0, or both. If the Internet address is equal to INADDR_ANY, any appropriate network interface will be used; this simplifies application programming in the presence of multihomed hosts. If the port is specified as 0, SOCKETS will assign a unique port to the application. The application may use getsockname() after bind() to learn the address that has been assigned to it, but note that getsockname() will not necessarily fill in the Internet address until the socket is connected, since several Internet addresses may be valid if the host is multi-homed.

See Also
connect(), listen(), getsockname(), setsockopt(), socket().
closesocket

Syntax:

```c
int closesocket ( SOCKET so )
```

Description:
Closes a socket.

Parameters Description

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>so</td>
<td>A descriptor identifying a socket.</td>
</tr>
</tbody>
</table>

Return Value
If no error occurs, `closesocket()` returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes

<table>
<thead>
<tr>
<th>Error Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ENETDOWN</td>
<td>SOCKETS has detected that the network subsystem has failed.</td>
</tr>
<tr>
<td>ENOTSOCK</td>
<td>The descriptor is not a socket.</td>
</tr>
<tr>
<td>EWOULDBLOCK</td>
<td>The socket is marked as nonblocking and SO_LINGER is set to a nonzero timeout value.</td>
</tr>
</tbody>
</table>

Remarks
This function closes a socket. More precisely, it releases the socket descriptor so, so that further references to so will fail with the error ENOTSOCK. If this is the last reference to the underlying socket, the associated naming information and queued data are discarded.

The semantics of `closesocket()` are affected by the socket options SO_LINGER and SO_DONTLINGER as follows:

<table>
<thead>
<tr>
<th>Option</th>
<th>Interval</th>
<th>Type of close</th>
<th>Wait for close?</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO_DONTLINGER</td>
<td>Don't care</td>
<td>Graceful</td>
<td>No</td>
</tr>
<tr>
<td>SO_LINGER</td>
<td>Zero</td>
<td>Hard</td>
<td>No</td>
</tr>
<tr>
<td>SO_LINGER</td>
<td>Non-zero</td>
<td>Graceful</td>
<td>Yes</td>
</tr>
</tbody>
</table>

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If SO_LINGER is set (i.e. the l_onoff field of the linger structure is non-zero) with a zero timeout interval (l_linger is zero), closesocket() is not blocked even if queued data has not yet been sent or acknowledged. This is called a "hard" or "abortive" close, because the socket's virtual circuit is reset immediately, and any unsent data is lost. Any recv() call on the remote side of the circuit will fail with ECONNRESET.

If SO_LINGER is set with a non-zero timeout interval, the closesocket() call blocks until the remaining data has been sent or until the timeout expires. This is called a graceful disconnect. Note that if the socket is set to non-blocking and SO_LINGER is set to a non-zero timeout, the call to closesocket() will fail with an error of EWOULDBLOCK.

If SO_DONTLINGER is set on a stream socket (i.e. the l_onoff field of the linger structure is zero), the closesocket() call will return immediately. However, any data queued for transmission will be sent if possible before the underlying socket is closed. This is also called a graceful disconnect. Note that in this case SOCKETS may not release the socket and other resources for an arbitrary period, which may affect applications which expect to use all available sockets.

See Also
accept(), socket(), ioctlsocket(), setsockopt.
connect

Syntax:
int connect ( SOCKET so, const struct sockaddr * psAddress, int iAddressLen )

Description:
Establishes a connection to a peer.

Parameters Description
so A descriptor identifying an unconnected socket.
psAddress The socket address of the peer to which the socket is to be connected.
iAddressLen The length of psAddress.

Return Value
If no error occurs, connect() returns 0. Otherwise, it returns SOCKET_ERROR, and a specific error code is returned in errno.

On a blocking socket, the return value indicates success or failure of the connection attempt.

On a non-blocking socket, if the return value is SOCKET_ERROR and errno indicates an error code of EWOULDBLOCK, then your application can either:

1. Use select() to determine the completion of the connection request by checking if the socket is writeable, or
2. Use recv() until either no error or an error of EWOULDBLOCK is returned.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EADDRINUSE The specified address is already in use.
EADDRNOTAVAIL The specified address is not available from the local machine.
EAFNOSUPPORT Addresses in the specified family cannot be used with this socket.
ECONNREFUSED The attempt to connect was forcefully
rejected.
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<table>
<thead>
<tr>
<th>Error Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>EDESTADDRREQ</td>
<td>A destination address is required.</td>
</tr>
<tr>
<td>EFAULT</td>
<td>The iAddressLen argument is incorrect.</td>
</tr>
<tr>
<td>EINVAL</td>
<td>The socket is not already bound to an address.</td>
</tr>
<tr>
<td>EISCONN</td>
<td>The socket is already connected.</td>
</tr>
<tr>
<td>EMFILE</td>
<td>No more file descriptors are available.</td>
</tr>
<tr>
<td>ENETUNREACH</td>
<td>The network can't be reached from this host at this time.</td>
</tr>
<tr>
<td>ENOBUFFS</td>
<td>No buffer space is available. The socket cannot be connected.</td>
</tr>
<tr>
<td>ENOTSOCK</td>
<td>The descriptor is not a socket.</td>
</tr>
<tr>
<td>ETIMEDOUT</td>
<td>Attempt to connect timed out without establishing a connection</td>
</tr>
<tr>
<td>EWOULDBLOCK</td>
<td>The socket is marked as non-blocking and the connection cannot be completed</td>
</tr>
<tr>
<td></td>
<td>immediately. It is possible to select() the socket while it is connecting</td>
</tr>
<tr>
<td></td>
<td>by select()ing it for writing.</td>
</tr>
</tbody>
</table>

**Remarks**

This function is used to create a connection to the specified foreign socket address. The parameter so specifies an unconnected datagram or stream socket. If the socket is unbound, unique values are assigned to the local association by the system, and the socket is marked as bound. Note that if the address field of the psAddress structure is all zeroes, `connect()` will return the error EADDRNOTAVAIL.

For stream sockets (type SOCK_STREAM), an active connection is initiated to the foreign host using psAddress (an address in the name space of the socket). When the socket call completes successfully, the socket is ready to send/receive data.

For a datagram socket (type SOCK_DGRAM), a default destination is set, which will be used on subsequent `send()` and `recv()` calls.

**See Also**

`accept()`, `bind()`, `getsockname()`, `socket()` and `select()`.
getpeername

Syntax:

```c
int getpeername ( SOCKET so, struct sockaddr * psAddress, int * piAddressLen )
```

Description:

Gets the socket address of the peer to which a socket is connected.

**Parameters Description**

- `so`: A descriptor identifying a connected socket.
- `psAddress`: The structure which is to receive the socket address of the peer.
- `piAddressLen`: A pointer to the size of the `psAddress` structure.

**Return Value**

If no error occurs, `getpeername()` returns 0. Otherwise, a value of `SOCKET_ERROR` is returned, and a specific error code is returned in `errno`.

**Error Codes**

- **ENETDOWN**: SOCKETS has detected that the network subsystem has failed.
- **EFAULT**: The `piAddressLen` argument is not large enough.
- **ENOTCONN**: The socket is not connected.
- **ENOTSOCK**: The descriptor is not a socket.

**Remarks**

`getpeername()` retrieves the socket address of the peer connected to the socket `so` and stores it in the struct `sockaddr` identified by `psAddress`. It is used on a connected datagram or stream socket.

On return, the `piAddressLen` argument contains the actual size of the socket address returned in bytes.

**See Also**

`bind()`, `socket()`, `getsockname()`.
getsockname

Syntax:
int getsockname ( SOCKET so, struct sockaddr * psAddress, int * piAddressLen )

Description:
Gets the local socket address for a socket.

Parameters Description
so A descriptor identifying a bound socket.
psAddress Receives the socket address (name) of the socket.
piAddressLen A pointer to the size of the psAddress buffer.

Return Value
If no error occurs, getsockname() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EFAULT The *piAddressLen argument is not large enough.
ENOTSOCK The descriptor is not a socket.
EINVAL The socket has not been bound to an address with bind().

Remarks
getsockname() retrieves the current socket address for the specified socket descriptor in psAddress. It is used on a bound and/or connected socket specified by the so parameter. The local association is returned. This call is especially useful when a connect() call has been made without doing a bind() first; this call provides the only means by which you can determine the local association which has been set by the system.
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On return, the piAddressLen argument contains the actual size of the socket address returned in bytes. If a socket was bound to INADDR_ANY, indicating that any of the host's IP addresses should be used for the socket, `getsockname()` will not necessarily return information about the host IP address, unless the socket has been connected with `connect()` or `accept()`. A SOCKETS application must not assume that the IP address will be changed from INADDR_ANY unless the socket is connected. This is because for a multi-homed host the IP address that will be used for the socket is unknown unless the socket is connected.

See Also
bind(), socket(), getpeername().
getsockopt

Syntax:
int getsockopt ( SOCKET so, int iLevel, int iOptname, char * pcOptval, int * piOptlen )

Description:
Retrieves a socket option.

Parameters Description
so A descriptor identifying a socket.
iLevel The level at which the option is defined; the only supported levels are
        SOL_SOCKET and IPPROTO_TCP.
iOptname The socket option for which the value is to be retrieved.
pcOptval A pointer to the buffer in which the value for the requested option is to be returned.
piOptlen A pointer to the size of the pcOptval buffer.

Return Value
If no error occurs, getsockopt() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EFAULT The piOptlen argument was invalid.
ENOPROTOOPT The option is unknown or unsupported. In particular, SO_BROADCAST is not supported on sockets of type SOCK_STREAM, while
        SO_ACCEPTCONN, SO_DONTLINGER, SO_KEEPALIVE, SO_LINGER and
        SO_OOBINLINE are not supported on sockets of type SOCK_DGRAM.
ENOTSOCK The descriptor is not a socket.
**Remarks**

`getsockopt()` retrieves the current value for a socket option associated with a socket of any type, in any state, and stores the result in `pcOptval`. Options may exist at multiple protocol levels, but they are always present at the uppermost "socket" level. Options affect socket operations, such as whether an operation blocks or not, the routing of packets, out-of-band data transfer, etc.

The value associated with the selected option is returned in the buffer `pcOptval`. The integer pointed to by `piOptlen` should originally contain the size of this buffer; on return, it will be set to the size of the value returned. For `SO_LINGER`, this will be the size of a struct linger; for all other options it will be the size of an integer.

If the option was never set with `setsockopt()`, then `getsockopt()` returns the default value for the option. The following options are supported for `getsockopt()`.

<table>
<thead>
<tr>
<th>Value</th>
<th>Type</th>
<th>Meaning</th>
<th>Default</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO_ACCEPTCONN</td>
<td>BOOL</td>
<td>Socket is listening.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_BROADCAST</td>
<td>BOOL</td>
<td>Socket is configured for the transmission of broadcast messages.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_DEBUG</td>
<td>BOOL</td>
<td>Debugging is enabled.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_DONTLINGER</td>
<td>BOOL</td>
<td>If true, the SO_LINGER option is disabled.</td>
<td>TRUE</td>
</tr>
<tr>
<td>SO_DONTRoute</td>
<td>BOOL</td>
<td>Routing is disabled.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_ERROR</td>
<td>int</td>
<td>Retrieve error status and clear.</td>
<td>0</td>
</tr>
<tr>
<td>SO_KEEPALIVE</td>
<td>BOOL</td>
<td>Keepalives are being sent.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_LINGER</td>
<td>struct linger*</td>
<td>Returns the current linger options.</td>
<td>_l_onoff is 0</td>
</tr>
<tr>
<td>SO_OOBINLINE</td>
<td>BOOL</td>
<td>Out-of-band data is being received in the normal data stream.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_RCVBUF</td>
<td>int</td>
<td>Buffer size for receives</td>
<td>1460</td>
</tr>
<tr>
<td>SO_REUSEADDR</td>
<td>BOOL</td>
<td>The socket may be bound to an address which is already in use.</td>
<td>FALSE</td>
</tr>
<tr>
<td>SO_SNDBUF</td>
<td>int</td>
<td>Buffer size for sends</td>
<td>1460</td>
</tr>
<tr>
<td>SO_TYPE</td>
<td>int</td>
<td>The type of the socket (e.g. SOCK_STREAM).</td>
<td>As created</td>
</tr>
<tr>
<td>TCP_NODELAY</td>
<td>BOOL</td>
<td>Disables the Nagle algorithm for send coalescing.</td>
<td>FALSE</td>
</tr>
</tbody>
</table>

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Calling `getsockopt()` with an unsupported option will result in an error code of ENOPROTOOPT being returned from `WSAGetLastError()`.

**See Also**
`setsockopt()`, `socket()`.
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htonl

Syntax:
u_long htonl ( u_long ulHostlong )

Description:
Converts a u_long from host to network byte order.

Parameters Description
ulHostlong A 32-bit number in host byte order.

Return Value
htonl() returns the value in network byte order.

Remarks
This routine takes a 32-bit number in host byte order and returns a 32-bit number in network byte order.

See Also
htonl(), ntohl(), ntohs().
htons

Syntax
u_short htons ( u_short usHostshort )

Description:
Converts a u_short from host to network byte order.

Parameters | Description
--- | ---
sHostshort | A 16-bit number in host byte order.

Return Value
htons() returns the value in network byte order.

Remarks
This routine takes a 16-bit number in host byte order and returns a 16-bit number in network byte order.

See Also
htonl(), ntohl(), ntohs().
inet_addr

Syntax:
unsigned long inet_addr ( const char * pc )

Description:
Converts a string containing a dotted address into an in_addr.

Parameters Description
pc A character string representing a number expressed in the Internet standard "." notation.

Return Value
If no error occurs, inet_addr() returns an unsigned long containing a suitable binary representation of the Internet address given. If the passed-in string does not contain a legitimate Internet address, for example if a portion of an "a.b.c.d" address exceeds 255, inet_addr() returns the value INADDR_NONE.

Remarks
This function interprets the character string specified by the pc parameter. This string represents a numeric Internet address expressed in the Internet standard "." notation. The value returned is a number suitable for use as an Internet address. All Internet addresses are returned in network order (bytes ordered from left to right).

Internet Addresses

Values specified using the "." notation take one of the following forms:

    a.b.c.d a.b.c a.b a

When four parts are specified, each is interpreted as a byte of data and assigned, from left to right, to the four bytes of an Internet address. Note that when an Internet address is viewed as a 32-bit integer quantity on the Intel architecture, the bytes referred to above appear as "d.c.b.a". That is, the bytes on an Intel processor are ordered from right to left.

Note: The following notations are only used by Berkeley, and nowhere
else on the Internet. In the interests of compatibility with their software, they are supported as specified.
Chapter 5 Programming and Function Library

When a three part address is specified, the last part is interpreted as a 16-bit quantity and placed in the right most two bytes of the network address. This makes the three part address format convenient for specifying Class B network addresses as "128.net.host".

When a two part address is specified, the last part is interpreted as a 24-bit quantity and placed in the right most three bytes of the network address. This makes the two part address format convenient for specifying Class A network addresses as "net.host".

When only one part is given, the value is stored directly in the network address without any byte rearrangement.

See Also
inet_ntoa()
Chapter 5 Programming and Function Library

inet_ntoa

Syntax:
char * inet_ntoa ( struct in_addr sIn )

Description:
Converts a network address into a string in dotted format.

Parameters Description
sIn A structure which represents an Internet host address.

Return Value
If no error occurs, inet_ntoa() returns a char pointer to a static buffer containing the text address in standard "." notation. Otherwise, it returns NULL. The data should be copied before another SOCKETS call is made.

Remarks
This function takes an Internet address structure specified by the sIn parameter. It returns an ASCII string representing the address in "." notation as "a.b.c.d". Note that the string returned by inet_ntoa() resides in memory which is allocated by SOCKETS. The application should not make any assumptions about the way in which the memory is allocated. The data is guaranteed to be valid until the next SOCKETS API call, but no longer.

See Also
inet_addr().
ioctlsocket

Syntax:
int ioctlsocket ( SOCKET so, long lCmd, u_long * pulArgp )

Description:
Controls the mode of a socket.

Parameters | Description
--- | ---
so | A descriptor identifying a socket.
lCmd | The command to perform on the socket so.
pulArgp | A pointer to a parameter for lCmd.

Return Value
Upon successful completion, the ioctlsocket() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
- ENETDOWN: SOCKETS has detected that the network subsystem has failed.
- EINVAL: lCmd is not a valid command, or pulArgp is not an acceptable parameter for lCmd, or the command is not applicable to the type of socket supplied.
- ENOTSOCK: The descriptor so is not a socket.

Remarks
This routine may be used on any socket in any state. It is used to get or retrieve operating parameters associated with the socket, independent of the protocol and communications subsystem. The following commands are supported:

<table>
<thead>
<tr>
<th>Command</th>
<th>Semantics</th>
</tr>
</thead>
<tbody>
<tr>
<td>FIONBIO</td>
<td>Enable or disable non-blocking mode on the so. pulArgp points at an unsigned long, which is non-zero if non-blocking mode is to be enabled and zero if it is to be disabled. When a socket is created, it operates in blocking mode (i.e. non-blocking mode is disabled). This is consistent</td>
</tr>
</tbody>
</table>
Chapter 5 Programming and Function Library

FIONREAD  Determine the amount of data which can be read atomically from socket so. pulArgp points at an unsigned long in which ioctlssocket() stores the result. If so is of type SOCK_STREAM, FIONREAD returns the total amount of data which may be read in a single recv(); this is normally the same as the total amount of data queued on the socket. If so is of type SOCK_DGRAM, FIONREAD returns the size of the first datagram queued on the socket.

SIOCATMARK  Determine whether or not all out-of-band data has been read. This applies only to a socket of type SOCK_STREAM which has been configured for in-line reception of any out-of-band data (SO_OOBINLINE). If no out-of-band data is waiting to be read, the operation returns TRUE. Otherwise it returns FALSE, and the next recv() or recvfrom() performed on the socket will retrieve some or all of the data preceding the "mark"; the application should use the SIOCATMARK operation to determine whether any remains. If there is any normal data preceding the "urgent" (out of band) data, it will be received in order. (Note that a recv() or recvfrom() will never mix out-of-band and normal data in the same call.) argp points at a BOOL in which ioctlssocket() stores the result.

Compatibility
This function is a subset of ioctl() as used in Berkeley sockets. In particular, there is no command which is equivalent to FIOASYNC, while SIOCATMARK is the only socketlevel command which is supported.

See Also
socket(), setsockopt(), getsockopt().

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listen

Syntax:
int listen ( SOCKET so, int iBacklog )

Description:
Establishes a socket to listen for incoming connection.

Parameters Description
so A descriptor identifying a bound, unconnected socket.
iBacklog The maximum length to which the queue of pending connections may grow.

Return Value
If no error occurs, listen() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EADDRINUSE An attempt has been made to listen() on an address in use.
EINVAL The socket has not been bound with bind() or is already connected.
EISCONN The socket is already connected.
EMFILE No more file descriptors are available.
ENOBUFS No buffer space is available.
ENOTSOCK The descriptor is not a socket.
EOPNOTSUPP The referenced socket is not of a type that supports the listen() operation.

Remarks
To accept connections, a socket is first created with socket(), a backlog for incoming connections is specified with listen(), and then the connections are accepted with accept().
listen() applies only to sockets that support connections, i.e. those of type SOCK_STREAM. The socket so is put into "passive" mode where incoming connections are acknowledged and queued pending acceptance by the process. This function is typically used by servers that could have more than one connection request at a time: if a connection request arrives with the queue full, the client will receive an error with an
Chapter 5 Programming and Function Library

indication of ECONNREFUSED.
Compatibility

iBacklog is limited (silently) to 5. As in 4.3BSD, illegal values (less than 1 or greater than 5) are replaced by the nearest legal value.

See Also

accept(), connect(), socket().
ntohl

Syntax:
\texttt{u\_long ntohl ( u\_long ulNetlong )}

Description:
Converts a \texttt{u\_long} from network to host byte order.

Parameters Description
\texttt{ulNetlong} A 32-bit number in network byte order.

Return Value
\texttt{ntohl()} returns the value in host byte order.

Remarks
This routine takes a 32-bit number in network byte order and returns a 32-bit number in host byte order.

See Also
\texttt{htonl()}, \texttt{htons()}, \texttt{ntohs()}. 
ntohs

Syntax
u_short ntohs ( u_short usNetshort )

Description:
Converts a u_short from network to host byte order.

Return Value
ntohs() returns the value in host byte order.

Parameters Description
usNetshort A 16-bit number in network byte order.

Remarks
This routine takes a 16-bit number in network byte order and returns a 16-bit number in host byte order.

See Also
htonl(), htons(), ntohl().
recv

Syntax:
int recv ( SOCKET so, char * pcbuf, int iLen, int iFlags )

Description:
Receives data from a socket.

Parameters Description
so A descriptor identifying a connected socket.
pcBuf A buffer for the incoming data.
iLen The length of pcBuf.
iFlags Specifies the way in which the call is made.

Return Value
If no error occurs, recv() returns the number of bytes received. If the connection has been closed, it returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
ENOTCONN The socket is not connected.
ENOTSOCK The descriptor is not a socket.
EOPNOTSUPP MSG_OOB was specified, but the socket is not of type SOCK_STREAM.
ESHUTDOWN The socket has been shutdown; it is not possible to recv() on a socket after shutdown() has been invoked with how set to 0 or 2.
EWOULDBLOCK The socket is marked as non-blocking and the receive operation would block.
EMSGSIZE The datagram was too large to fit into the specified buffer and was truncated.
EINVAL The socket has not been bound with bind().
ECONNABORTED The virtual circuit was aborted due to timeout or other failure.
ECONNRESET The virtual circuit was reset by the remote side.
Remarks
This function is used on connected datagram or stream sockets specified by the so parameter and is used to read incoming data.

For sockets of type SOCK_STREAM, as much information as is currently available up to the size of the buffer supplied is returned. If the socket has been configured for in-line reception of out-of-band data (socket option SO_OOBINLINE) and out-of-band data is unread, only out-of-band data will be returned. The application may use the ioctlsocket() SIOCATMARK to determine whether any more out-of-band data remains to be read.

For datagram sockets, data is extracted from the first enqueued datagram, up to the size of the buffer supplied. If the datagram is larger than the buffer supplied, the buffer is filled with the first part of the datagram, the excess data is lost, and recv() returns the error EMSGSIZE.

If no incoming data is available at the socket, the recv() call waits for data to arrive unless the socket is non-blocking. In this case a value of SOCKET_ERROR is returned with the error code set to EWOULDBLOCK. The select() call may be used to determine when more data arrives.

If the socket is of type SOCK_STREAM and the remote side has shut down the connection gracefully, a recv() will complete immediately with 0 bytes received. If the connection has been reset, a recv() will fail with the error ECONNRESET.

iFlags may be used to influence the behavior of the function invocation beyond the options specified for the associated socket. That is, the semantics of this function are determined by the socket options and the iFlags parameter. The latter is constructed by or-ing any of the following values:

<table>
<thead>
<tr>
<th>Value</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSG_PEEK</td>
<td>Peek at the incoming data. The data is copied into the buffer but is not removed from the input queue.</td>
</tr>
<tr>
<td>MSG_OOB</td>
<td>Process out-of-band data.</td>
</tr>
</tbody>
</table>

See Also
recvfrom(), recv(), send(), select(), socket()
recvfrom

Syntax
int recvfrom ( SOCKET so, char * pcBuf, int iLen, int iFlags, struct sockaddr * psFrom, int * piFromlen )

Description:
Receives a datagram and store the source address.

Parameters Description
so A descriptor identifying a bound socket.
pcBuf A buffer for the incoming data.
iLen The length of pcBuf.
iFlags Specifies the way in which the call is made.
psFrom An optional pointer to a buffer which will hold the source address upon return.
piFromlen An optional pointer to the size of the psFrom buffer.

Return Value
If no error occurs, recvfrom() returns the number of bytes received. If the connection has been closed, it returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EFAULT The piFromlen argument was invalid: the psFrom buffer was too small to accommodate the peer address.
EINVAL The socket has not been bound with bind().
ENOTCONN The socket is not connected (SOCK_STREAM only).
ENOTSOCK The descriptor is not a socket.
EOPNOTSUPP MSG_OOB was specified, but the socket is not of type SOCK_STREAM.
ESHUTDOWN The socket has been shutdown; it is not possible to recvfrom() on a socket after shutdown() has been invoked with how set to 0 or 2.
EWOULDBLOCK The socket is marked as non-blocking.
Chapter 5 Programming and Function Library
and the recvfrom() operation would block.
Chapter 5 Programming and Function Library

EMSGSIZE  The datagram was too large to fit into the specified buffer and was truncated.
ECONNABORTED  The virtual circuit was aborted due to timeout or other failure.
ECONNRESET  The virtual circuit was reset by the remote side.

Remarks
This function is used to read incoming data on a (possibly connected) socket and capture the address from which the data was sent.

For sockets of type SOCK_STREAM, as much information as is currently available up to the size of the buffer supplied is returned. If the socket has been configured for in-line reception of out-of-band data (socket option SO_OOBINLINE) and out-of-band data is unread, only out-of-band data will be returned. The application may use the ioctlsocket() SIOCATMARK to determine whether any more out-of-band data remains to be read. The psFrom and piFromlen parameters are ignored for SOCK_STREAM sockets.

For datagram sockets, data is extracted from the first enqueued datagram, up to the size of the buffer supplied. If the datagram is larger than the buffer supplied, the buffer is filled with the first part of the message, the excess data is lost, and recvfrom() returns the error code EMSGSIZE.

If psFrom is non-zero, and the socket is of type SOCK_DGRAM, the network address of the peer which sent the data is copied to the corresponding struct sockaddr. The value pointed to by piFromlen is initialized to the size of this structure, and is modified on return to indicate the actual size of the address stored there.

If no incoming data is available at the socket, the recvfrom() call waits for data to arrive unless the socket is non-blocking. In this case a value of SOCKET_ERROR is returned with the error code set to EWOULDBLOCK. The select() call may be used to determine when more data arrives.

If the socket is of type SOCK_STREAM and the remote side has shut down the connection gracefully, a recvfrom() will complete immediately with 0 bytes received. If the connection has been reset recv() will fail with the error ECONNRESET.
iFlags may be used to influence the behavior of the function invocation beyond the options specified for the associated socket. That is, the semantics of this function are determined by the socket options and the iFlags parameter. The latter is constructed by or-ing any of the following values:

<table>
<thead>
<tr>
<th>Value</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSG_PEEK</td>
<td>Peek at the incoming data. The data is copied into the buffer but is not removed from the input queue.</td>
</tr>
<tr>
<td>MSG_OOB</td>
<td>Process out-of-band data.</td>
</tr>
</tbody>
</table>

See Also
recv(), send(), socket().
select

Syntax:
int select ( int iNfds, fd_set * psReadfds, fd_set * psWritefds, fd_set * psExceptfds, const struct timeval * psTimeout )

Description:
Determines the status of one or more sockets, waiting if necessary.

Parameters Description
iNfds This argument is ignored and included only for the sake of compatibility.
psReadfds An optional pointer to a set of sockets to be checked for readability.
psWritefds An optional pointer to a set of sockets to be checked for writability
psExceptfds An optional pointer to a set of sockets to be checked for errors.
psTimeout The maximum time for select() to wait, or NULL for blocking operation.

Return Value
select() returns the total number of descriptors which are ready and contained in the fd_set structures, 0 if the time limit expired, or SOCKET_ERROR if an error occurred. If the return value is SOCKET_ERROR, errno contains the specific error code.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
EINVAL The psTimeout value is not valid.
ENOTSOCK One of the descriptor sets contains an entry which is not a socket.
Remarks
This function is used to determine the status of one or more sockets. For each socket, the caller may request information on read, write or error status. The set of sockets for which a given status is requested is indicated by an fd_set structure. Upon return, the structure is updated to reflect the subset of these sockets which meet the specified condition, and select() returns the number of sockets meeting the conditions. A set of macros is provided for manipulating an fd_set. These macros are compatible with those used in the Berkeley software, but the underlying representation is completely different and the same as that used in Winsock.

The parameter psReadfds identifies those sockets which are to be checked for readability. If the socket is currently listen()ing, it will be marked as readable if an incoming connection request has been received, so that an accept() is guaranteed to complete without blocking. For other sockets, readability means that queued data is available for reading or, for sockets of type SOCK_STREAM, that the virtual socket corresponding to the socket has been closed, so that a recv() or recvfrom() is guaranteed to complete without blocking. If the virtual circuit was closed gracefully, then a recv() will return immediately with 0 bytes read; if the virtual circuit was reset, then a recv() will complete immediately with the error code ECONNRESET. The presence of out-of-band data will be checked if the socket option SO_OOBINLINE has been enabled (see setsockopt()).

The parameter psWritefds identifies those sockets which are to be checked for writability. If a socket is connect()ing (non-blocking), writability means that the connection establishment successfully completed. If the socket is not in the process of connect()ing, writability means that a send() or sendto() will complete without blocking.

The parameter psExceptionfds identifies those sockets which are to be checked for the presence of out-of-band data or any exceptional error conditions. Note that out-of-band data will only be reported in this way if the option SO_OOBINLINE is FALSE. For a SOCK_STREAM, the breaking of the connection by the peer or due to KEEPALIVE failure will be indicated as an exception. If a socket is connect()ing (non-blocking), failure of the connect attempt is indicated in psExceptionfds.
Any of psReadfds, psWritefds, or psExceptfds may be given as NULL if no descriptors are of interest.

Four macros are defined in the header file socket.h for manipulating the descriptor sets. The variable FD_SETSIZE determines the maximum number of descriptors in a set. (The default value of FD_SETSIZE is 16, which may be modified by defining FD_SETSIZE to another value before #including socket.h.) Internally, an fd_set is represented as an array of SOCKETs. The macros are:

- FD_CLR(so, *psSet) Removes the descriptor so from set.
- FD_ISSET(so, *psSet) Nonzero if so is a member of the set, zero otherwise.
- FD_SET(so, *psSet) Adds descriptor so to set.
- FD_ZERO(*psSet) Initializes the set to the NULL set.

The parameter psTimeout controls how long the select() may take to complete. If psTimeout is a null pointer, select() will block indefinitely until at least one descriptor meets the specified criteria. Otherwise, psTimeout points to a struct timeval which specifies the maximum time that select() should wait before returning. If the timeval is initialized to {0, 0}, select() will return immediately; this is used to "poll" the state of the selected sockets.

See Also
accept(), connect(), recv(), recvfrom(), send().
send

Syntax:
int send ( SOCKET so, const char * pcBuf, int iLen, int iFlags )

Description:
Sends data on a connected socket.

Parameters | Description
---|---
so | A descriptor identifying a connected socket.
pcBuf | A buffer containing the data to be transmitted.
iLen | The length of the data in pcBuf.
iFlags | Specifies the way in which the call is made.

Return Value
If no error occurs, send() returns the total number of characters sent. (Note that this may be less than the number indicated by len.) Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN | SOCKETS has detected that the network subsystem has failed.
EACCES | The requested address is a broadcast address, but the appropriate flag was not set.
EFAULT | The pcBuf argument is not in a valid part of the user address space.
ENETRESET | The connection must be reset because SOCKETS dropped it.
ENOBUSYS | SOCKETS reports a buffer deadlock.
ENOTCONN | The socket is not connected.
ENOTSOCK | The descriptor is not a socket.
EOPNOTSUPP | MSG_OOB was specified, but the socket is not of type SOCK_STREAM.
ESHUTDOWN | The socket has been shutdown; it is not possible to send() on a socket after shutdown() has been invoked with how set to 1 or 2.
EWOULDBLOCK | The socket is marked as non-blocking
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and the requested operation would block.

EMSGSIZE The socket is of type SOCK_DGRAM, and the datagram is larger than the maximum supported by SOCKETS.
EINVAL The socket has not been bound with bind().
ECONNABORTED The virtual circuit was aborted due to timeout or other failure.
ECONNRESET The virtual circuit was reset by the remote side.

Remarks
send() is used on connected datagram or stream sockets and is used to write outgoing data on a socket. For datagram sockets, care must be taken not to exceed the maximum IP packet size of the underlying subnets. If the data is too long to pass atomically through the underlying protocol the error EMSGSIZE is returned, and no data is transmitted.

Note that the successful completion of a send() does not indicate that the data was successfully delivered.

If no buffer space is available within the transport system to hold the data to be transmitted, send() will block unless the socket has been placed in a non-blocking I/O mode. On non-blocking SOCK_STREAM sockets, the number of bytes written may be between 1 and the requested length, depending on buffer availability on both the local and foreign hosts. The select() call may be used to determine when it is possible to send more data.

iFlags may be used to influence the behavior of the function invocation beyond the options specified for the associated socket. That is, the semantics of this function are determined by the socket options and the flags parameter. The latter is constructed by oring any of the following values:

<table>
<thead>
<tr>
<th>Value</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSG_DONTROUTE</td>
<td>Specifies that the data should not be subject to routing</td>
</tr>
<tr>
<td>MSG_OOB</td>
<td>Send out-of-band data (SOCK_STREAM only)</td>
</tr>
</tbody>
</table>

See Also
recv(), recvfrom(), socket(), sendto().
sendto

Syntax:
int sendto ( SOCKET so, const char * pcBuf, int iLen, int iFlags, const struct sockaddr * psTo, int iTolen )

Description:
Sends data to a specific destination.

Parameters | Description
--- | ---
so | A descriptor identifying a socket.
pcBuf | A buffer containing the data to be transmitted.
iLen | The length of the data in pcBuf.
iFlags | Specifies the way in which the call is made.
PsTo | An optional pointer to the address of the target socket.
iTolen | The size of the address in to.

Return Value
If no error occurs, sendto() returns the total number of characters sent. (Note that this may be less than the number indicated by len.) Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
- ENETDOWN: SOCKETS has detected that the network subsystem has failed.
- EACCES: The requested address is a broadcast address, but the appropriate flag was not set.
-EFAULT: The pcBuf or psTo parameters are not part of the user address space, or the psTo argument is too small (less than the sizeof a struct sockaddr).
- ENETRESET: The connection must be reset because SOCKETS dropped it.
- ENOBUFFS: SOCKETS reports a buffer deadlock.
- ENOTCONN: The socket is not connected (SOCK_STREAM only).
- ENOTSOCK: The descriptor is not a socket.
- EOPNOTSUPP: MSG_OOB was specified, but the socket is not of type SOCK_STREAM.
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<table>
<thead>
<tr>
<th>Error Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ESHUTDOWN</td>
<td>The socket has been shutdown; it is not possible to sendto() on a socket after shutdown() has been invoked with how set to 1 or 2.</td>
</tr>
<tr>
<td>EWOULD(Block</td>
<td>The socket is marked as non-blocking and the requested operation would block.</td>
</tr>
<tr>
<td>EMSGSIZE</td>
<td>The socket is of type SOCK_DGRAM, and the datagram is larger than the maximum supported by SOCKETS.</td>
</tr>
<tr>
<td>ECONNABORTED</td>
<td>The virtual circuit was aborted due to timeout or other failure.</td>
</tr>
<tr>
<td>ECONNRESET</td>
<td>The virtual circuit was reset by the remote side.</td>
</tr>
<tr>
<td>EADDRNOTAVAIL</td>
<td>The specified address is not available from the local machine.</td>
</tr>
<tr>
<td>EAFNOSUPPORT</td>
<td>Addresses in the specified family cannot be used with this socket.</td>
</tr>
<tr>
<td>EDESTADDRREQ</td>
<td>A destination address is required.</td>
</tr>
<tr>
<td>ENETUNREACH</td>
<td>The network can't be reached from this host at this time.</td>
</tr>
</tbody>
</table>

**Remarks**

sendto() is used on datagram or stream sockets and is used to write outgoing data on a socket. For datagram sockets, care must be taken not to exceed the maximum IP packet size of the underlying subnets. If the data is too long to pass atomically through the underlying protocol the error EMSGSIZE is returned, and no data is transmitted.

Note that the successful completion of a sendto() does not indicate that the data was successfully delivered.

sendto() is normally used on a SOCK_DGRAM socket to send a datagram to a specific peer socket identified by the psTo parameter. On a SOCK_STREAM socket, the psTo and iTolen parameters are ignored; in this case the sendto() is equivalent to send().

To send a broadcast (on a SOCK_DGRAM only), the address in the to parameter should be constructed using the special IP address INADDR_BROADCAST (defined in socket.h) together with the intended port number. It is generally inadvisable for a broadcast datagram to exceed the size at 5-168 ADAM-4500 Series User’s Manual.
which fragmentation may occur, which implies that the data portion of the datagram (excluding headers) should not exceed 512 bytes.
If no buffer space is available within the transport system to hold the data to be transmitted, `sendto()` will block unless the socket has been placed in a non-blocking I/O mode. On non-blocking SOCK_STREAM sockets, the number of bytes written may be between 1 and the requested length, depending on buffer availability on both the local and foreign hosts. The `select()` call may be used to determine when it is possible to send more data.

`iFlags` may be used to influence the behavior of the function invocation beyond the options specified for the associated socket. That is, the semantics of this function are determined by the socket options and the `iFlags` parameter. The latter is constructed by or-ing any of the following values:

<table>
<thead>
<tr>
<th>Value</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>MSG_DONTROUTE</td>
<td>Specifies that the data should not be subject to routing.</td>
</tr>
<tr>
<td>MSG_OOB</td>
<td>Send out-of-band data (SOCK_STREAM only Out of band data)</td>
</tr>
</tbody>
</table>

See Also
recv(), recvfrom(), socket(), send().
setsockopt

Syntax:
int setsockopt ( SOCKET so, int level, int optname, const char * optval, int optlen )

Description:
Sets a socket option.

Parameters Description
so       A descriptor identifying a socket.
level    The level at which the option is defined; the only supported levels are
         SOL_SOCKET and IPPROTO_TCP.
optname  The socket option for which the value is to be set.
optval   A pointer to the buffer in which the value for the requested option is supplied.
optlen   The size of the optval buffer.

Return Value
If no error occurs, setsockopt() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
ENETDOWN  SOCKETS has detected that the network subsystem has failed.
EFAULT    optval is not in a valid part of the process address space.
EINVAL    level is not valid, or the information in optval is not valid.
ENETRESET Connection has timed out when SO_KEEPALIVE is set.
ENOPROTOOPT The option is unknown or unsupported. In particular, SO_BROADCAST is not supported on sockets of type SOCK_STREAM, while
            SO_DONTLINGER, SO_KEEPALIVE, SO_LINGER and SO_OOBINLINE are not supported on sockets of type SOCK_DGRAM.
ENOTCONN  Connection has been reset when SO_KEEPALIVE is set.
ENOTSOCK

The descriptor is not a socket.
Remarks

setsockopt() sets the current value for a socket option associated with a socket of any type, in any state. Although options may exist at multiple protocol levels, this specification only defines options that exist at the uppermost "socket" level. Options affect socket operations, such as whether expedited data is received in the normal data stream, whether broadcast messages may be sent on the socket, etc.

There are two types of socket options: Boolean options that enable or disable a feature or behavior, and options which require an integer value or structure. To enable a Boolean option, optval points to a nonzero integer. To disable the option optval points to an integer equal to zero. optlen should be equal to sizeof(int) for Boolean options. For other options, optval points to the an integer or structure that contains the desired value for the option, and optlen is the length of the integer or structure.

SO_LINGER controls the action taken when unsent data is queued on a socket and a closesocket() is performed. See closesocket() for a description of the way in which the SO_LINGER settings affect the semantics of closesocket(). The application sets the desired behavior by creating a struct linger (pointed to by the optval argument) with the following elements:

```c
struct linger
{
    int l_onoff;
    int l_linger;
};
```

To enable SO_LINGER, the application should set l_onoff to a non-zero value, set l_linger to 0 or the desired timeout (in seconds), and call setsockopt(). To enable SO_DONTLINGER (i.e. disable SO_LINGER) l_onoff should be set to zero and setsockopt() should be called.

By default, a socket may not be bound (see bind()) to a local address which is already in use. On occasions, however, it may be desirable to "re-use" an address in this way. Since every connection is uniquely identified by the combination of local and remote addresses, there is no problem with having two sockets bound to the same local address as long as the remote addresses are different. To inform SOCKETS that a bind() on a socket should not be disallowed because the desired address is already in use by another socket, the application should set the SO_REUSEADDR
socket option for the socket before
issuing the `bind()` function. Note that the option is interpreted only at the time of the `bind()`; it is therefore unnecessary (but harmless) to set the option on a socket which is not to be bound to an existing address, and setting or resetting the option after the `bind()` has no effect on this or any other socket.

An application may request that SOCKETS enable the use of "keep-alive" packets on TCP connections by turning on the SO_KEEPALIVE socket option. If a connection is dropped as the result of "keep-alives" the error code ENETRESET is returned to any calls in progress on the socket, and any subsequent calls will fail with ENOTCONN.

The TCP_NODELAY option disables the Nagle algorithm. The Nagle algorithm is used to reduce the number of small packets sent by a host by buffering unacknowledged send data until a full-size packet can be sent. However, for some applications this algorithm can impede performance, and TCP_NODELAY may be used to turn it off. Application writers should not set TCP_NODELAY unless the impact of doing so is well-understood and desired, since setting TCP_NODELAY can have a significant negative impact of network performance. TCP_NODELAY is the only supported socket option which uses `level` IPPROTO_TCP; all other options use `level` SOL_SOCKET.

The following options are supported for `setsockopt()`. The Type identifies the type of data addressed by `optval`.

<table>
<thead>
<tr>
<th>Value</th>
<th>Type</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO_BROADCAST</td>
<td>BOOL</td>
<td>Allow transmission of broadcast messages on the socket.</td>
</tr>
<tr>
<td>SO_DEBUG</td>
<td>BOOL</td>
<td>Record debugging information.</td>
</tr>
</tbody>
</table>
| SO_DONTLINGER     | BOOL    | Don't block close waiting for unsent data to be sent. Setting this option is equivalent to setting SO_LINGER with `l_onoff` set to zero.
| SO_DONTROUTE      | BOOL    | Don't route; send directly to interface.                                |
| SO_KEEPALIVE      | BOOL    | Send keepalives                                                        |
| SO_LINGER         | struct linger * | Linger on close if unsent data is present                             |
| SO_OOBINLINE      | BOOL    | Receive out-of-band data in the normal data stream.                     |
| SO_RCVBUF         | Int     | Specify buffer size for receives                                       |
| SO_REUSEADDR      | BOOL    | Allow the socket to be bound to an address which is already in use.    |

(See `bind()`.)
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<table>
<thead>
<tr>
<th>Variable</th>
<th>Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO_SNDBUF</td>
<td>Int</td>
<td>Specify buffer size for sends.</td>
</tr>
<tr>
<td>TCP_NODELAY</td>
<td>BOOL</td>
<td>Disables the Nagle algorithm for send coalescing.</td>
</tr>
</tbody>
</table>

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BSD options not supported for `setsockopt()` are:

<table>
<thead>
<tr>
<th>Value</th>
<th>Type</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>SO_ACCEPTCONN</td>
<td>BOOL</td>
<td>Socket is listening</td>
</tr>
<tr>
<td>SO_ERROR</td>
<td>Int</td>
<td>Get error status and clear</td>
</tr>
<tr>
<td>SO_RCVLOWAT</td>
<td>Int</td>
<td>Receive low water mark</td>
</tr>
<tr>
<td>SO_RCVTIMEO</td>
<td>Int</td>
<td>Receive timeout</td>
</tr>
<tr>
<td>SO_SNDLOWAT</td>
<td>Int</td>
<td>Send low water mark</td>
</tr>
<tr>
<td>SO_SNDTIMEO</td>
<td>Int</td>
<td>Send timeout</td>
</tr>
<tr>
<td>SO_TYPE</td>
<td>Int</td>
<td>Type of the socket</td>
</tr>
<tr>
<td>IP_OPTIONS</td>
<td></td>
<td>Set options field in IP header.</td>
</tr>
</tbody>
</table>

**See Also**

`bind()`, `getsockopt()`, `ioctlsocket()`, `socket()`.
shutdown

Syntax:
int shutdown ( SOCKET so, int how )

Description:
Disables sends and/or receives on a socket.

Parameters | Description
--- | ---
so | A descriptor identifying a socket.
how | A flag that describes what types of operation will no longer be allowed.

Return Value
If no error occurs, shutdown() returns 0. Otherwise, a value of SOCKET_ERROR is returned, and a specific error code is returned in errno.

Error Codes
- ENETDOWN: SOCKETS has detected that the network subsystem has failed.
- EINVAL: how is not valid.
- ENOTCONN: The socket is not connected (SOCK_STREAM only).
- ENOTSOCK: The descriptor is not a socket.

Remarks
shutdown() is used on all types of sockets to disable reception, transmission, or both. If how is 0, subsequent receives on the socket will be disallowed. This has no effect on the lower protocol layers. For TCP, the TCP window is not changed and incoming data will be accepted (but not acknowledged) until the window is exhausted. For UDP, incoming datagrams are accepted and queued. In no case will an ICMP error packet be generated.

If how is 1, subsequent sends are disallowed. For TCP sockets, a FIN will be sent. Setting how to 2 disables both sends and receives as described above. Note that shutdown() does not close the socket, and resources attached to the socket will not be freed until closesocket() is invoked.
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Comments

shutdown() does not block regardless of the SO_LINGER setting on the socket. An application should not re-use a socket after it has been shut down.

See Also
connect(), socket().
socket

Syntax:
SOCKET socket ( int af, int type, int protocol )

Description:
Creates a socket.

Parameters
- **af**: An address format specification. The only format currently supported is PF_INET, which is the ARPA Internet address format.
- **type**: A type specification for the new socket.
- **protocol**: A particular protocol to be used with the socket, or 0 if the caller does not wish to specify a protocol.

Return Value
If no error occurs, **socket()** returns a descriptor referencing the new socket. Otherwise, a value of INVALID_SOCKET is returned, and a specific error code is returned in errno.

Error Codes
- **ENETDOWN**: SOCKETS has detected that the network subsystem has failed.
- **EAFNOSUPPORT**: The specified address family is not supported.
- **EMFILE**: No more file descriptors are available.
- **ENOBUFFS**: No buffer space is available. The socket cannot be created.
- **EPROTONOSUPPORT**: The specified protocol is not supported.
- **EPROTOTYPE**: The specified protocol is the wrong type for this socket.
- **ESOCKTNOSUPPORT**: The specified socket type is not supported in this address family.

Remarks
**socket()** allocates a socket descriptor of the specified address family, data type and protocol, as well as related resources. If a protocol is not specified (i.e. equal to 0), the default for the specified connection mode is used.
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Only a single protocol exists to support a particular socket type using a given address format. However, the address family may be given as AF_UNSPEC (unspecified), in which case the protocol parameter must be specified. The protocol number to use is particular to the "communication domain" in which communication is to take place.

The following type specifications are supported:

**Type Explanation**

<table>
<thead>
<tr>
<th>Type</th>
<th>Explanation</th>
</tr>
</thead>
<tbody>
<tr>
<td>SOCK_STREAM</td>
<td>Provides sequenced, reliable, two-way, connection-based byte streams with an out-of-band data transmission mechanism. Uses TCP for the Internet address family.</td>
</tr>
<tr>
<td>SOCK_DGRAM</td>
<td>Supports datagrams, which are connectionless, unreliable buffers of a fixed (typically small) maximum length. Uses UDP for the Internet address family.</td>
</tr>
</tbody>
</table>

Sockets of type SOCK_STREAM are full-duplex byte streams. A stream socket must be in a connected state before any data may be sent or received on it. A connection to another socket is created with a `connect()` call. Once connected, data may be transferred using `send()` and `recv()` calls. When a session has been completed, a `closesocket()` must be performed. Out-of-band data may also be transmitted as described in `send()` and received as described in `recv()`.

The communications protocols used to implement a SOCK_STREAM ensure that data is not lost or duplicated. If data for which the peer protocol has buffer space cannot be successfully transmitted within a reasonable length of time, the connection is considered broken and subsequent calls will fail with the error code set to ETIMEDOUT.

SOCK_DGRAM sockets allow sending and receiving of datagrams to and from arbitrary peers using `sendto()` and `recvfrom()`. If such a socket is `connect()`ed to a specific peer, datagrams may be send to that peer `send()` and may be received from (only) this peer using `recv()`.

**See Also**

`accept()`, `bind()`, `connect()`, `getsockname()`, `getsockopt()`, `setsockopt()`, `listen()`, `recv()`, `recvfrom()`, `select()`, `send()`, `sendto()`
shutdown(),
ioctlsocket().
gethostbyaddr

Syntax:
struct hostent * gethostbyaddr ( const char * pcAddr, int len, int type )

Description:
Gets host information corresponding to an address.

Parameters Description
pcAddr A pointer to an address in network byte order.
len The length of the address, which must be 4 for PF_INET addresses.
type The type of the address, which must be PF_INET.

Return Value
If no error occurs, gethostbyaddr() returns a pointer to the hostent structure described above. Otherwise it returns a NULL pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
WSAHOST_NOT_FOUND Authoritative Answer Host not found.
WSATRY_AGAIN Non-Authoritative Host not found, or SERVERFAIL.
WSANO_RECOVERY Non-recoverable errors, FORMERR, REFUSED, NOTIMP.
WSANO_DATA Valid name, no data record of requested type.

Remarks
gethostbyaddr() returns a pointer to the following structure which contains the name(s) and address which correspond to the given address.

struct hostent
{
    char * h_name;
    char ** h_aliases;
    short h_addrtype;
}
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short h_length;
char ** h_addr_list;

};
The members of this structure are:

<table>
<thead>
<tr>
<th>Element</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>h_name</td>
<td>Official name of the host (PC).</td>
</tr>
<tr>
<td>h_aliases</td>
<td>A NULL-terminated array of alternate names.</td>
</tr>
<tr>
<td>h_addrtype</td>
<td>The type of address being returned; for SOCKETS this is always PF_INET.</td>
</tr>
<tr>
<td>h_length</td>
<td>The length, in bytes, of each address; for PF_INET, this is always 4.</td>
</tr>
<tr>
<td>h_addr_list</td>
<td>A NULL-terminated list of addresses for the host.</td>
</tr>
</tbody>
</table>

Addresses are returned in network byte order.

The macro h_addr is defined to be h_addr_list[0] for compatibility with older software. The pointer which is returned points to a structure which is allocated by SOCKETS. The application must never attempt to modify this structure or to free any of its components. The application should copy any information which it needs before issuing any other SOCKETS API calls.

**See Also**

cgettext()
gethostbyname

Syntax:
struct hostent * gethostbyname ( const char * pszName )

Description:
Gets host information corresponding to a hostname.

Parameters Description
PszName     A pointer to the name of the host.

Return Value
If no error occurs, gethostbyname() returns a pointer to the hostent structure described above. Otherwise it returns a NULL pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN    SOCKETS has detected that the network subsystem has failed.
WSAHOST_NOT_FOUND Authoritative Answer Host not found.
WSATRY_AGAIN Non-Authoritative Host not found, or SERVERFAIL.
WSANO_RECOVERY Non recoverable errors, FORMERR, REFUSED, NOTIMP.
WSANO_DATA    Valid name, no data record of requested type.

Remarks
gethostbyname() returns a pointer to a hostent structure as described under gethostbyaddr(). The contents of this structure correspond to the hostname pszName. The pointer which is returned points to a structure which is allocated by SOCKETS. The application must never attempt to modify this structure or to free any of its components. The application should copy any information which it needs before issuing any other SOCKETS API calls.
A gethostbyname() implementation must not resolve IP address strings passed to it. Such a request should be treated exactly as if an unknown host name were passed. An application with an IP address string to resolve should use inet_addr() to convert the string to an IP address, then gethostbyaddr() to obtain the hostent structure.

See Also
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gethostbyaddr()
**gethostname**

**Syntax:**
```c
int gethostname ( char * pszName, int iAddressLen )
```

**Description:**
Return the standard host name for the local machine.

**Parameters Description**
- **pszName**
  A pointer to a buffer that will receive the host name.
- **iAddressLen**
  The length of the buffer.

**Return Value**
If no error occurs, `gethostname()` returns 0, otherwise it returns `SOCKET_ERROR` and a specific error code is returned in `errno`.

**Error Codes**
- **EFAULT**
  The `iAddressLen` parameter is too small
- **ENETDOWN**
  SOCKETS has detected that the network subsystem has failed.

**Remarks**
This routine returns the name of the local host into the buffer specified by the `pszName` parameter. The host name is returned as a null-terminated string. The form of the host name is dependent on the SOCKETS configuration file. However, it is guaranteed that the name returned will be successfully parsed by `gethostbyname()`.

**See Also**
`gethostbyname()`.
getprotobynamel

Syntax:
struct protoent * getprotobynamel ( const char * pszName )

Description:
Gets protocol information corresponding to a protocol name.

Parameters Description
pszName A pointer to a protocol name.

Return Value
If no error occurs, getprotobynamel() returns a pointer to the protoent structure described above. Otherwise it returns a NULL pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
WSANO_RECOVERY Non recoverable errors, FORMERR, REFUSED, NOTIMP.
WSANO_DATA Valid name, no data record of requested type.

Remarks
getprotobynamel() returns a pointer to the following structure which contains the name(s) and protocol number which correspond to the given protocol pszName.

struct protoent
{ char * p_name;
  char ** p_aliases;
  short p_proto;
};

The members of this structure are:

Element Usage
p_name Official name of the protocol.
p_aliases A NULL-terminated array of alternate names.
p_proto The protocol number, in host byte order.
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The pointer which is returned points to a structure which is allocated by the SOCKETS library. The application must never attempt to modify this structure or to free any of its components. The application should copy any information which it needs before issuing any other SOCKETS API calls.

See Also
getprotobynumber()
getprotobynumber

Syntax:
struct protoent * getprotobynumber ( int number )

Description:
Gets protocol information corresponding to a protocol number.

Parameters Description
number A protocol number, in host byte order.

Return Value
If no error occurs, getprotobynumber() returns a pointer to the protoent structure described above. Otherwise it returns a NULL pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
WSANO_RECOVERY Non recoverable errors, FORMERR, REFUSED, NOTIMP.
WSANO_DATA Valid name, no data record of requested type.

Remarks
This function returns a pointer to a protoent structure as described above in getprotobyname(). The contents of the structure correspond to the given protocol number.

The pointer which is returned points to a structure which is allocated by SOCKETS. The application must never attempt to modify this structure or to free any of its components. The application should copy any information which it needs before issuing any other SOCKETS API calls.

See Also
getprotobyname()
getservbyname

Syntax:
struct servent * getservbyname ( const char * pszName, const char * proto )

Description:
Gets service information corresponding to a service name and protocol.

Parameters Description
pszName A pointer to a service name.
proto An optional pointer to a protocol name. If this is NULL, getservbyname() returns the first service entry for which the pszName matches the s_name or one of the s_aliases. Otherwise getservbyname() matches both the pszName and the proto.

Return Value
If no error occurs, getservbyname() returns a pointer to the servent structure described above. Otherwise it returns a NULL pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN SOCKETS has detected that the network subsystem has failed.
WSANO_RECOVERY Non recoverable errors, FORMERR, REFUSED, NOTIMP.
WSANO_DATA Valid name, no data record of requested type.

Remarks
getservbyname() returns a pointer to the following structure which contains the name(s) and service number which correspond to the given service pszName.

struct servent
{
    char * s_name;
    char ** s_aliases;
    short s_port;
    char * s_proto;
};

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The members of this structure are:

<table>
<thead>
<tr>
<th>Element</th>
<th>Usage</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_name</td>
<td>Official name of the service.</td>
</tr>
<tr>
<td>s_aliases</td>
<td>A NULL-terminated array of alternate names.</td>
</tr>
<tr>
<td>s_port</td>
<td>The port number at which the service can be contacted. Port numbers are returned in network byte order.</td>
</tr>
<tr>
<td>s_proto</td>
<td>The name of the protocol to use when contacting the service.</td>
</tr>
</tbody>
</table>

The pointer which is returned points to a structure which is allocated by the SOCKETS library. The application must never attempt to modify this structure or to free any of its components. The application should copy any information which it needs before issuing any other SOCKETS API calls.

**See Also**

getservbyport()
getservbyport

Syntax
struct servent * getservbyport ( int port, const char * proto )

Description:
Gets service information corresponding to a port and protocol.

Parameters Description
Port The port for a service, in network byte order.
Proto An optional pointer to a protocol name. is
NULL, getservbyport() returns the first service
entry for which the port matches the s_port. Otherwise getservbyport() matches both
the port and the proto.

Return Value
If no error occurs, getservbyport() returns a pointer to the
servent structure described above. Otherwise it returns a NULL
pointer and a specific error number is returned in errno.

Error Codes
ENETDOWN SOCD侩S has detected that
the network subsystem has failed.
WSANO_RECOVERY Non recoverable errors, FORMERR,
REFUSED, NOTIMP.
WSANO_DATA Valid name, no data record of
requested type.

Remarks
getservbyport() returns a pointer a servent structure as
described above for getservbyname().

The pointer which is returned points to a structure which is allocated
by SOCKETS. The application must never attempt to
modify this structure or to free any of its components. The
application should copy any information which it needs before
issuing any other SOCKETS API calls.

See Also
getservbyname()
5.3.7 HTTP Functions (CGI_LIB*.LIB)

CGI Application API (Server API)

Introduction

The SOCKETS web servers, HTTPD.EXE and HTTPFTPD.EXE, provide both a Spawning Common Gateway Interface (CGI) and an Extention API with the ability to extend the server to create dynamic web pages, perform specialized tasks, etc. One of the extentions provided is a Server Side Includes (SSI) interface using the CGI interface, enabling a user to create web pages using HTML templates with variable names, which is substituted in-time with specific values. The HTTPD Extension CGI works as follows: The extension has to implement one function called the callback function. The server has a number of functions that the extension may use, e.g. HttpSendData. They are designed to give the extension sufficient control over any http request.

Spawning CGI

An external program, indicated by the requested URL, is spawned. All relevant information is passed as environment variables. The program gets all input (e.g. posted data) from standard in and sends all response through standard out.

This type of CGI is discouraged in favor of the Extension API.

The following CGI environment variables are supported:

CONTENT_TYPE
CONTENT_LENGTH
PATH, COMSPEC
REQUEST_METHOD

Enough free memory must be available when spawning a CGI program, or no swapping or overlaying will be attempted. Since COMMAND.COM uses all free memory, it follows that no CGI program will be spawned if COMMAND.COM is the current foreground program.
CGI programs must be small and must execute reasonably quickly. While a CGI program is executing, the HTTP server is effectively blocked and cannot service any other requests. No console input or output should be used. A CGI program is invoked by a URL containing a path of /cgi-bin/<cgi-program> where <cgi-program> is the name of an executable program which must be in the HTTP root directory or in the path. Note that the "/cgi-bin/" part is stripped off and does not represent a real directory. <Cgi-program> may be followed by a "?" and a command line. On entry to the CGI program, the environment variables listed above are set up and can be accessed.

If a command line is given, it can also be accessed in the normal way. The CGI program generates a dynamic page by writing to STDOUT. When the CGI program terminates, this output is sent to the remote client (browser). The output can consist of a header and a body part separated by an empty line. If the header contains a "Content-type:" line, the content type will be set to that type and only the body will be sent to the client. Otherwise all the output will be sent to the client using content type “text/plain”. COMMAND.COM can be invoked as a CGI program to perform simple DOS functions e.g. directory listings. The following example performs a directory listing:

http://www.embedded-server.com/cgi-bin/command/?/cdir

The next one performs a wide directory listing using a wild-card specification:

http://www.embedded-server.com/cgi-bin/command/?/cdir%20*.htm%20/w

Note the use of %20 to specify a space character.

Refer to the INDEX.HTM web page for an example of various ways of calling CGI programs. The NUM.EXE program with source code NUM.C, demonstrates the use of a header and body part building a simple "page visited" web page:

printf("Content-type: text/html\n\n" ";<html><h1>
This page has been visited %d times<h1>
", number);
printf("<P><A HREF="/index.htm">Back</A>.
\n")};
Forms programming can be performed using either the GET or POST methods. When GET is used, form data is copied to the command line and is limited to 128 characters including the URL part. When the POST method is used, the command line is also built. In addition, form data are available from STDIN and is limited by disk space only.

See the forms programming example consisting of FORM.HTM, FORM.EXE and FORM.C for examples of using both the GET and POST methods. So that you may fully understand CGI programming, this detailed explanation of the server operation is provided.

Whenever HTTPD receives a URL containing “/cgi-bin/”, it interprets the rest of the URL as a DOS program to spawn and run to completion. The full path parsed from the URL is used, implying that the program should be in physical directory called “/cgi-bin/” or a subdirectory thereof. E.g. “program.exe” should be in “%HTTP_DIR%/cgi-bin/” if the request is “GET /cgi-bin/program.exe”.

While this “CGI program” is executing, the server can accept new server connections, but will not respond to them before the CGI program terminates. The CGI program can be any DOS program that is small enough to fit into available memory. Since HTTPD is blocked while the CGI program executes, user interaction should not be used and the CGI program should complete in a reasonable time.

Operation on receiving a CGI URL:

If the CGI program name is followed by a “?” , the rest of the line is sent as a command line to the CGI program after converting all %n combinations.

If a “Content-Type” header is encountered, the CONTENT_TYPE environment variable is set to the given value and if a “Content-Length” header is encountered, the CONTENT_LENGTH environment variable is set to the given value. The PATH and COMSPEC environment variables are copied to the new environment and the REQUEST_METHOD environment variable is set to either GET or POST.

If the POST method is used, the rest of the HTTP message is copied
to a temporary file that is then re-directed to stdin. The stdout stream is redirected to another temporary file. After completion of the request, the temporary files are deleted. They will be created in the %HTTPTMP% directory.
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The CGI program is now invoked. This program can check the environment variables, access the command line and in the case of a POST, read from stdin.

All output that should be passed back to the HTTP client (Browser) is written to stdout. A single header line followed by an empty line, containing “Contenttype:

```
ccontent_type````
```
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```
The Callback function will be called when a request for the registered path is received and as many times afterwards as is necessary to complete the request. It is called with a parameter structure specifying the reason for the request, the User ID, an HTTPD handle and values specific to the reason for the callback, e.g. a pointer to the command line on the initial callback. Other reasons for calling the Callback function are to notify of new received data, connection closure by the peer, readiness to accept more data and connection errors.

The callback must return a value to indicate that it is still busy handling the request, has completed the request or wants to abort the request with an error. The HTTPD handle will be constant and unique from the first callback to the completion of the request.

While in the Callback function, data can be read from the peer or sent to the peer and a file can be submitted to be sent to the peer.

**Note:** Extensions are responsible for sending all HTTP header fields to clients.

The following extensions have been developed for functional and demonstrational purposes.

**SSI Interface**

If you want to display the current date and time, or a certain CGI environment variable in your otherwise static document, you can go through the trouble of writing a CGI program that outputs this small amount of virtual data. Or better yet, you can use a powerful feature called Server Side Includes (or SSI).

Server Side Includes are directives which you can place into your HTML documents to output such data as environment variables and file statistics. For a detailed introduction, please visit [http://www.ora.com/info/cgi/ch05.html](http://www.ora.com/info/cgi/ch05.html)

A simple yet powerful interface is provided to perform Server Side Includes (SSI) tasks. A user only has to implement one predefined function and make use of only four API functions to unlock the power of SSI. The working of the interface is described at the 5-200 ADAM-4500 Series User’s Manual
To use, include ssicgi.c in your project and include ssi.h in your source files. Take a look at ssi.c for a simple example.
Five very simple examples are included to demonstrate the usage of the Extention API. Source code is included, as well as make files. Put all .htm and .exe files in the %HTTP_DIR% directory and start HTTPD. Load all the cgi programs (you may use cgi.bat). All is in place now and the examples may be accessed through index.htm.

The first four examples may operate in one of two modes:

- As a TSR (resident) program: this is the default behavior. At this stage unloading of the TSR is not supported. De-registration is possible by loading the program again. This routine may be repeated.

- As a transient program: use ‘/t’ command line switch to activate. This option will immediately spawn ‘command.com’. From this prompt other cgi programs may be loaded. The program exits when ‘command.com’ is exited by typing ‘exit’ at the prompt.

These programs are:

1. **cgiecho** A very simple program that accepts data from a user and echoes it back nicely formatted. Get echoform.htm from the browser.
2. **cgicount** A page visit counter. Only updates between sessions if transient (cgicount /t). Get num.htm from the browser.
3. **cgiform** Does the same as the old ‘fill out the form and submit’ utility. Get caform.htm from the browser.

**SSI** A very simple SSI implementation that demonstrates the SSI interfaces. Template.htm is filled by some variables. Get ssi.htm from the browser.

The fifth example, **FFUR**, (Form-base File Upload Receiver) is only a transient program, but can easily be adapted to be similar to the rest. It handles the upload of a file as a POST command by filling out ffur.htm.
Chapter 5 Programming and Function Library

HTTPD Function Reference

CGIADAP.C is an interface program a user may utilize to implement external extension CGI programs. This interface performs stack and context switches, and provides ordinary C functions to access the http server (HTTPD.exe).

The header file to use is CGIADAP.H.

The API may be used without using CGIADAP by making low-level calls which are detailed below. In this case the user must perform the required stack and context switches if required.
### HttpRegister

**Syntax:**
```c
int HttpRegister(char far *szPath, int (far *pfCallback)(HTTP_PARAMS far *psHttpParams), int iFlags, DWORD dwUserID)
```

**Description:**
The HttpRegister() function registers an interest in a URL, providing a callback function. The callback is guaranteed to only be called when DOS can be called. The DOS critical handler will be disabled and all critical errors will result in an access error without any user intervention. Since the callback happens at interrupt time, it should execute for as short a time as possible. After a done or error return, no further callbacks will be generated for the current request. Only one callback will be active at any time. Calling an API function while executing the callback function will not result in another callback before the current callback has returned.

**Parameters Description**

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>szPath</td>
<td>Far pointer to the string identifying a URL. It should be an exact match of the abs_path part of the URI minus the leading '/'. For instance, if you want to capture all <a href="http://myserver.com/cgi-bin/getpage.exe">http://myserver.com/cgi-bin/getpage.exe</a>, you should register 'cgibin/getpage.exe'.</td>
</tr>
<tr>
<td>pfCallback</td>
<td>Address of callback function. Return values when returning from callback: RET_OK not done, give me more upcalls RET_DONE done, no more upcalls please RET_ERR done, error</td>
</tr>
<tr>
<td>psHttpParams</td>
<td>Far pointer to HTTP parameter block. psHttpParams-&gt;iReason Reason for callback: R_NEWREQ - New HTTP request. pszCommandLine points to the command line passed in the URL. The number contained in iValue specifies the HTTP operation; RQ_GET for GET and RQ_POST for POST. R_INDATA - Input data available, iValue contains count.</td>
</tr>
</tbody>
</table>

---

5-204 ADAM-4500 Series User’s Manual
Chapter 5 Programming and Function Library

R_OUTDATA - Can send output data, iValue contains count.
R_ENDDATA - Peer closed connection i.e. "end of input data"
R_CLOSED - Connection closed.
psHttpParams->iHandle
HTTPD handle, used in subsequent API calls for this request. The user should not modify it. See HTAPICH for the other definitions

iflags
F_OVERLAP - Overlapped request (1),
non-overlapped request (0).
All other bits are reserved.

dwUserID
Value passed to HttpRegister(); this value is for use by the extension, HTTPD does not modify it.

Return value
0 OK
< 0 One of the error messages (SEE HTAPICH)

Low level calling parameters
AH APIF_REGISTER (0)
DS:SI szPath
ES:DI pfCallback
BX iFlags
CX:DX dwUserID

Low level return parameters
Return code in AX.

Note that the stack and the data segment on entry will be that of HTTPD. Depending on the memory model used for the extension and the amount of stack space required, it may be required to switch stacks during the callback.
HttpDeRegister

Syntax:
int HttpDeRegister(char far *pszPath)

Description:
The HttpDeRegister() function removes the interest in a URL. After this call no more callbacks will be generated for this URL. Any requests in progress will be terminated with an error to the peer. This function must be called for all registrations made by a program before terminating that program; otherwise the system will inevitably crash on any subsequent request.

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pszPath</td>
<td>Far pointer to URL to de-register.</td>
</tr>
</tbody>
</table>

Return value
0        OK
< 0      One of the error messages (SEE HTAPIC.H)

Low level calling parameters
AH       APIF_DEREGISTER (1)
DS:SI    pszPath

Low level return parameters
Return code in AX.
HttpGetData

Syntax
int HttpGetData(int iHandle, char far *pcBuf, int iCount)

Description:
The HttpGetData() function can be called when a POST operation has been indicated by the callback to get data sent to the server by the client. If more data is expected and the extension is busy executing the callback function, a 0 return should be made from the callback indicating it is still busy and getting more data should be attempted at the next callback.

Parameter Description
iHandle Handle passed in pfsHttpParams.
pcBuf Far pointer to buffer to receive data.
iCount Length of buffer.

Return value
>=0 OK, number of bytes received.
< 0 One of the error messages (SEE HTAPIC.H)

Low level calling parameters
AH APIF_GETDATA (2)
BX iHandle
DS:SI pcBuf
CX iCount

Low level return parameters
Return code in AX.
HttpSendData

Syntax
int HttpSendData(int iHandle, char far *pcBuf, int iCount)

Description:
The HttpSendData() function is used to send data to the client. If the return indicates that less than the requested number of bytes has been sent and the extension is busy executing the callback function, a 0 return should be made from the callback indicating it is still busy. Then an attempt to send more data should be made at the next callback. All the required data should be sent to the client before an HttpSubmitFile() function is used. After HttpSubmitFile(), HttpSendData() should not be called again.

Parameter  | Description
---|---
iHandle | Handle passed in pfsHttpParams.
pcBuf | Far pointer to buffer with data to send.
iCount | Length of buffer.

Return value
>=0  Number of bytes actually sent
< 0  One of the error messages (SEE HTAPIC.H)

Low level calling parameters
AH      | APIF_SENDDATA (3)
BX      | iHandle
DS:SI   | pcBuf
CX      | iCount

Low level return parameters
Return code in AX.
## HttpSubmitFile

**Syntax:**

```c
int HttpSubmitFile(int iHandle, char far *pszFileName)
```

**Description:**

The HttpSubmitFile() function is used to submit a file to be sent to the client in response to a request. The file will be logically appended to any data already sent using HttpSendData(). The file should not be exclusively opened when it is submitted. After it is transmitted, transmit upcalls will be issued normally. This gives the user the ability to send any number of files on the connection with arbitrary data in between.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>iHandle</code></td>
<td>Handle passed in pfsHttpParams.</td>
</tr>
<tr>
<td><code>pszFileName</code></td>
<td>Far pointer to name of file to submit.</td>
</tr>
</tbody>
</table>

**Return value**

- 0: OK
- < 0: One of the error messages (SEE HTAPIC.H)

**Low level calling parameters**

- **AH**: APIF_SENDFILE (4)
- **BX**: `iHandle`
- **DS:SI**: `pszFileName`
Chapter 5 Programming and Function Library

**HttpGetStatus**

**Syntax**

```c
int HttpGetStatus(void)
```

**Description:**
The `HttpGetStatus()` function gets the number of connections to the server. It must also be used as a polling function when the server is running in passive mode to dequeue and handle pending requests.

**Parameters**
None.

**Return value**

- \( \geq 0 \)  Number of connections to server.
- \( < 0 \)  One of the error messages (SEE HTAPIC.H)

**Low level calling parameters**

```
AH  APiF_GETSTATUS(6)
```

**Low level return parameters**
Return code in AX.
HttpGetVersion

Syntax
int HttpGetVersion(void);

Description:
The `HttpGetVersion()` function gets the version of the running HTTP server.

Parameter
None.

Return value
>=0 Version number.
< 0 One of the error messages (SEE HTAPIC.H)

Low level calling parameters
AH APIF_GETVERSION (5)

Low level return parameters
Return code in AX.
GetStackPointer
GetStackSegment

Syntax
int GetStackPointer (void)
int GetStackSegment (void)

Description:
The GetStackPointer and GetStackSegment functions get the current Stack Pointer/Segment.

Parameters
None.

Return value
Current value of Stack Pointer/Segment.
SetStackPointer
SetStackSegment

Syntax:
void SetStackPointer (int iPointer)
void SetStackSegment (int iSegment)

Description:
The SetStackPointer and SetStackSegment functions set the Stack
Pointer/Segment. The stack pointer for callbacks is by default set to
_SP - 1000, the first time the HTTP API is called. If you would need
space on the stack, or for some reason want to make it tighter, set the
stack pointer for callbacks manually. Be careful not to overwrite used
memory.

<table>
<thead>
<tr>
<th>Parameters</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>iPointer</td>
<td>Value to set Stack Pointer to.</td>
</tr>
</tbody>
</table>

Return value
None.

Constants and Definitions used by CGI API
Refer to HTAPIC.H.

SSI Definitions and functions
Refer to SSI.H.
6

Sockets Utility
Chapter 6 Sockets Utility

SOCKETS utilities make use of command-line parameters and/or configuration files. Please be careful to note the name and location of the configuration file used by the application you are working with. All SOCKETS applications require that the kernel be loaded before the application is run in order to function properly. You can find all these SOCKETS utilities under C:\Program Files\Advantech\ADAM-4500 Series Utility\Source\Drive_D\Extension_files (Refer to image below). When you need to use the utilities, remember to download the execution file to ADAM-4500 Series Controller.
**DHCPSTAT**

DHCPSTAT displays the DHCP information for the machine.

**Syntax**

```
DHCPSTAT [r | v]
```

**Options**

- **r** force a renewal of the DHCP lease.
- **V** display the SOCKETS version information.

**Example**

```
DHCPSTAT
```

This will display all the DHCP information, such as IP address and lease time.
Chapter 6 Sockets Utility

FTP

FTP is a file transmitting and retrieving client that runs in interactive or batch mode.

Syntax
FTP server [options]

Options
/n
/v
/p=Port
/f=ScriptFile [ScriptParameters]

Remarks
Server
The name or IP address of a server you want to connect.
/n
 Suppress progress indicator.
/v
 Verbose output for troubleshooting.
/p=Port
 Connect to a server port other than the standard FTP port number of 21.
/f=ScriptFile
 A file containing commands for the client to send to the server upon connection. Simple parameter substitution is performed, with the first element of ScriptParameters accessible as “%1,” etc.

ScriptParameters
Parameters to pass into the ScriptFile.

Return Codes
0 Success
1 Parameter error
2 SOCKETS not loaded
3 User aborted
4 Transfer aborted
5 Error writing local file
6 Error reading local file

Other Server returned error response code; to find that error code, add 390 to the response code returned by FTP. The result will always be greater than or equal to 400 in this case.
Example

FTP /n FTP.cdrom.com /f=getfile.scr /2/simtelnet/msdos DIRS.TXT
(The file GETFILE.SCR):
user anonymous
pass root@
cd %1
binary
get %2
quit

FTP Commands

The commands entered at the FTP client can be interpreted and translated to standard FTP commands to be sent to the server. The FTP server might recognize more, or less, commands than the standard list of commands as specified in RFC 959. The site command is always server dependent. Some of the standard commands are implemented differently in various servers. Useful things to note are:

1. The put and get commands allow multiple file transfers by usage of wild card characters. When getting files with paths or long names, no translation of foreign file names is done. Specify a valid DOS local_file name.
2. A short directory list (NLST) is obtained by ls and the long list with dir.
3. Some of the commands can be abbreviated.
4. Some commands are aliases added for user comfort like bye, exit and quit; get and mget; and put and mput.
5. The optional [local_file] parameter will, when specified, cause the output of that command to be logged to a file. By specifying the file as PRN you can get immediate printouts.
6. On some servers you might specify the optional [remote_file] parameter as PRN or the printer output device to do remote printing. (See also the site nopath command for the SOCKETS FTP server.)
7. The F3 key and spacebar can be used to recall the last command word by word. Below is a list of commands recognized by the SOCKETS FTP client (some FTP servers might not offer all the facilities):
## Chapter 6 Sockets Utility

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>abort</td>
<td>Cancel an incomplete transfer</td>
</tr>
<tr>
<td>append</td>
<td>&quot;Put&quot; a file at the server but append it if the file exists</td>
</tr>
<tr>
<td>ascii</td>
<td>Synonym for type a</td>
</tr>
<tr>
<td>binary</td>
<td>Synonym for type i</td>
</tr>
<tr>
<td>bye</td>
<td>Synonym for quit</td>
</tr>
<tr>
<td>cd directory</td>
<td>Change server directory</td>
</tr>
<tr>
<td>cwd directory</td>
<td>Synonym for cwd</td>
</tr>
<tr>
<td>dele file</td>
<td>Delete a server file</td>
</tr>
<tr>
<td>dir [file</td>
<td>directory [local_file]]</td>
</tr>
<tr>
<td>exit</td>
<td>Synonym for quit</td>
</tr>
<tr>
<td>get remote_file(s) [local_file]</td>
<td>Transfer a file from the server in the current mode (type)</td>
</tr>
<tr>
<td>image</td>
<td>Synonym for type i</td>
</tr>
<tr>
<td>ls [file</td>
<td>directory [local_file]]</td>
</tr>
<tr>
<td>lcd directory</td>
<td>Perform a local change directory</td>
</tr>
<tr>
<td>ldir [file</td>
<td>directory]</td>
</tr>
<tr>
<td>list [file</td>
<td>directory [local_file]]</td>
</tr>
<tr>
<td>mget remote_file(s) [local_file]</td>
<td>Synonym for get</td>
</tr>
<tr>
<td>mkdir remote_directory</td>
<td>Create a server directory</td>
</tr>
<tr>
<td>mput local_file(s) [remote_file]</td>
<td>Synonym for put</td>
</tr>
<tr>
<td>nlst [file</td>
<td>directory [local_file]]</td>
</tr>
<tr>
<td>pass [password]</td>
<td>Password for username</td>
</tr>
<tr>
<td>pasv [on</td>
<td>off]</td>
</tr>
<tr>
<td>put local_file(s) [remote_file]</td>
<td>Transfer a file to the server in the current mode (type)</td>
</tr>
<tr>
<td>Pwd</td>
<td>Print working directory at server</td>
</tr>
<tr>
<td>quit</td>
<td>Terminate FTP session</td>
</tr>
<tr>
<td>quote remote_command [args ...]</td>
<td>Send a command to the server without any interpretation</td>
</tr>
<tr>
<td>rmdir remote_directory</td>
<td>Remove (delete) a server directory</td>
</tr>
<tr>
<td>rnfr existing_filename</td>
<td>Rename a file, command 1 of 2</td>
</tr>
<tr>
<td>rnto new_filename</td>
<td>Rename a file, command 2 of 2</td>
</tr>
<tr>
<td>site sub-command</td>
<td>Send server specific commands</td>
</tr>
<tr>
<td>size file</td>
<td>Report the file size in bytes as a 213 message</td>
</tr>
<tr>
<td>shell</td>
<td>Shell to DOS for IFTP.EXE</td>
</tr>
<tr>
<td>stat</td>
<td>Report the status of a transfer or active connections</td>
</tr>
<tr>
<td>System</td>
<td>Return operating system information from the server</td>
</tr>
<tr>
<td>type [i I a]</td>
<td>Report or select the file transfer mode: image (binary) or ASCII</td>
</tr>
<tr>
<td>user [username]</td>
<td>Username to logon</td>
</tr>
<tr>
<td>verbose [on</td>
<td>off]</td>
</tr>
</tbody>
</table>

---

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Chapter 6 Sockets Utility

**IFSTAT**

IFSTAT displays the status of the Interface and the version information for SOCKETS.

**Syntax**

`IFSTAT [i] [v]`

**Options**

- **i**: show the Interface status.
- **v**: show the version information.

**Example**

`IFSTAT v`

This will display the SOCKETS version information
Chapter 6 Sockets Utility

IPSTAT

The IPSTAT utility returns statistics on IP and memory. Use IPSTAT to check for error conditions and memory problems.

Syntax
IPSTAT

Example
IPSTAT

The following will be displayed (The values may differ):
IP stats at 160F:04C8:
Total Packets 2671
Smaller than minimum size 0
IP header length too small 0
Wrong IP version 0
Unsupported protocol 0
Memory available 9016
Memory allocation failures 0
Memory free errors 0
Minimum stack observed 886
MAKEMAIL

MAKEMAIL packages the body text and any attachments for delivery using the SENDMAIL application.

Syntax
MAKEMAIL –tToAddress –fFromAddress –sSubject –bBodyTextFile - oOutputFile aAttachment

Options
ToAddress
The e-mail address of the recipient(s) of this mail. Additional recipients are specified by repeated use of the –t parameter. If the ToAddress is a name that can be resolved by either the DNS server or host file then the @servername is not necessary.

FromAddress
Used to identify the sender of the message

Subject
The subject line of the e-mail message

BodyTextFile
The local file containing the body text of the e-mail message to deliver

OutputFile
The local file name in which to store the prepared file for delivery by SENDMAIL. This file is overwritten if it already exists!

Attachment
The name of a local file to be binary attached to this e-mail message. Multiple attachments are created by repeated use of the –a parameter. Files are attached as MIME parts, encoded with the application/x-uuencode content type.

Example

MAKEMAIL tfred@yahoo.com fmary@yahoo.com –sStatus – bmessage.txt –omail.dat


Chapter 6 Sockets Utility

**SENDMAIL**

SENDMAIL delivers e-mail messages packaged by the MAKEMAIL application to an Internet mail server. SENDMAIL also creates a local log file to indicate successful send or failures.

**Syntax**

SENDMAIL server file

**Options**

**Server**
The IP address or DNS name of the Internet mail server to receive the message.

**File**
The file created by the MAKEMAIL utility to deliver.

**Logging Format**

**Timestamp, Code String**

*Timestamp*
Weekday Month Day Time Year

*Code*
Three digit integer: 000 means perfect success, 100-199 mean usage error and 200-299 means TCP/IP error from server.

*String*
Human-readable explanation of the error code

**Example**

SENDMAIL mail.datalight.com mail.dat
Xping

Xping starts a continuous string of pings until stopped by a keystroke.

Syntax
Xping ip address [interval]

Remarks
ip address This may be a numeric address or a name address.

Options
interval The time to wait between pings in clock ticks.

Example
Xping 10.0.0.1 20
This will ping the address of 10.0.0.1 every 20 clock ticks.
HTTP and FTP Server Application
HTTP Server

Overview

The SOCKETS HTTP server, HTTPD.EXE, is a small, fast, reliable and extendable web server that can run as either an application or TSR. Apart from the minimum required file download capability, the following additional capabilities are provided:

1. **Remote Console Server** – ability to gain terminal-type access to the server system, using a standard browser, without the need to install any software on the browser computer.
2. **Authentication** – Both system wide and directory wise
3. **CGI Extendibility** – The ability to extend the server to create dynamic web pages, perform specialized tasks, etc.
4. A Server Side Includes (SSI) interface is provided using the CGI interface, enabling a user to create web pages using HTML templates with variable names substituted in-time with specific values.
5. Ability to run as a background process.
6. Flexibility to control physical parameters such as memory usage and number of connections.

Server

The HTTP server is used to send static web pages existing as files on the server or dynamically generated web pages to a remote client (browser). Dynamic pages can be generated in two ways:

1. **Extension CGI.** By calling an external CGI handler, the server provides an API to external handlers. A Server Side Includes (SSI) interface is provided as well, which makes it very easy to create powerful interactive web pages.
2. **Spawning CGI.** By spawning programs with a relatively short execution time to generate the pages through a mechanism similar to CGI, the basic mechanism used by CGI is that arbitrary programs can be spawned from the web server with input as received from the remote browser and output that can be sent to the browser.

The Remote Console Server accepts input from a remote client that is fed to the keyboard buffer for use by an arbitrary program using it. It also monitors the screen display buffer area and sends screen information to the remote client.
The SOCKETS password file controls authentication. Authentication is user specific and may also differ from directory to directory. It may also be put off for either some or all users. See the section on authentication.

The HTTP server can support multiple simultaneous sessions. The GET and POST request methods are implemented as well as the following MIME types: text/html, text/plain, image/gif, image/jpeg, image/jpg and application/octet-stream. The MIME type is determined by the file extension.

Remote Console Server

Initialization

The client (browser) will initialize a remote session. An HTTP connection will be made to the HTTP server. The downloaded page will contain the applet that will automatically connect to the RCS on TCP port 81. An example download page is supplied as REMCON.HTM.

Almost any application e.g. a text editor can be run on the server. The remote keyboard and display control the application as if they were locally attached.

On the remote side, the Java Applet acts as a simple terminal emulator that displays what it receives from the server and sends what is entered from the keyboard to the server.

It is not required to have a real display adapter on the embedded system server, only to have display buffer memory.

When a new connection is made, all the screen data, as well as the cursor position, is sent to the client. Subsequently the RCS keeps a watch on the video memory and cursor position and whenever a change is detected, the RCS sends the changed data to the Java applet.

Keyboard data received from the client is passed to the keyboard buffer making it available as keyboard input for use by any application executing on the server.
Remote Console Client

The remote console client exists as a Java 1.3.1 applet, supplied as RC.JAR, and will function on any Java 1.3.1 compliant browser. Please note that a security certificate has not been compiled into RC.JAR so it is not compliant with versions of the Netscape browser that require a security certificate to run Java applets. A DOS based client using SOCKETS is also supplied as RCCLI.EXE. For additional information about RC.JAR or RCCLI.EXE, please see the Utility Description Chapter.

Extension CGI

The SOCKETS HTTP servers (HTTPD/HTTPFTPD) provide a facility to call functions in other modules which may be TSR or transient programs. These functions are referred to as “HTTPD extensions.” For more information please see the “ROM - DOS Developer’s Guide” section “CGI Application API.

Extension CGI Examples

Five very simple examples are included to demonstrate the implementation of CGI. Source code is included.

Put all .htm and .exe files in the %HTTP_DIR% directory and start HTTPD. Load all the cgi programs (you may use cgi.bat). All is in place now and the examples may be accessed through index.htm.

The first four examples may operate in one of two modes:

As a TSR (resident) program: this is the default behavior. At this stage unloading of the TSR is not supported. De-registration is possible by loading the program again. This routine may be repeated.

As a transient program: use ‘/t’ command line switch to activate. This option will immediately spawn ‘command.com’. From this prompt other cgi programs may be loaded. The program exits when ‘command.com’ is exited by typing ‘exit’ at the prompt.

These programs are:

1. cgiecho A very simple program that accepts data from a user and echoes it back nicely formatted. Get echoform.htm from the browser.
2. **cgcicount**  A page visit counter. Only updates between sessions if transient (cgcicount /t). Get *num.htm* from the browser.

3. **cgiform**  Does the same as the old ‘fill out the form and submit’ utility. Get *caform.htm* from the browser.

4. **SSI**  A very simple SSI implementation demonstrating the SSI interfaces. *Template.htm* is filled by some variables. Get *ssi.htm* from the browser.

The fifth example, **FFUR**, (Form-base File Upload Receiver) is only a transient program, but can easily be adapted to be similar to the rest. It handles the upload of a file as a POST command by filling out *ffur.htm*.

---

**Passive Mode**

The server may be run in passive mode by specifying a ‘/p’ command line switch. When passive, the server will record network events but only handle them once it is triggered by a CGI user.

---

**Server Memory**

The server’s memory usage may be controlled in two ways:

1. By specifying the amount of memory when going TSR.

2. By specifying the maximum number of connections the server will allow.

Option 1 is the recommended option. Use Option 2 if you have ‘heavy’ web pages – usually the type where pages consist of frames and many images, etc. Connections are generally reset when more connections are attempted than the defined maximum. The client then must retry to establish the lost connections, leading to a more distributed load on the server.

---

**Spawning CGI**

An external program, indicated by the requested URL, is spawned. All relevant information is passed as environment variables. The CGI program gets all input (e.g. posted data) from *standard in* and sends all response through *standard out*. Spawning CGI is discouraged in favor of Extension CGI. For more information please see the “ROM - DOS Developer’s Guide” section “CGI Application API.”
Chapter 7 HTTP and FTP Server Application

Authentication

Default authentication matches the capabilities of the FTP server as documented in the section “FTP Server” on page 217. A file called "SOCKET.UPW" should exist in the SOCKETS (environment variable) directory.

The default permission file controls remote console access. Each listed user has a single -letter privilege code set if he has privilege to use the Remote Console. The code should be missing if that user does not have Remote Console privilege.

An additional authentication feature is implemented - htaccess. This feature provides a per-directory permission override mechanism. It is enabled using '/' as command line switch. If htaccess is enabled, the default mechanism may be skipped (but no default users or remote console access will be available).

A file called HTACCESS (typically hidden) contains authentication overrides to enable partial anonymous access or additional password security to subdirectories, etc. If this feature is activated, the server code will look for HTACCESS files in each directory starting from the requested path and continuing upward in the directory structure (assuming the root directory to be at the top) until an HTACCESS file is found. If no file is found, then the default settings are used. An anonymous access entry is available for the developer to specify that some subdirectory is authorized for any user, although its parent directory is password protected. CGI scripts can also be controlled via the HTACCESS mechanism.
Chapter 7 HTTP and FTP Server Application

HTTPD Program

The syntax for HTTPD is:

HTTPD [options] [<http_port>] [<rc_port>]

Any combination of these switches may be used. They should be separated by at least one space.

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>/? /h</td>
<td>Display help screen</td>
</tr>
<tr>
<td>/r</td>
<td>Run server in TSR mode</td>
</tr>
<tr>
<td>/s</td>
<td>Display server status</td>
</tr>
<tr>
<td>/t</td>
<td>Enable .htaccess directory level authentication</td>
</tr>
<tr>
<td>/u</td>
<td>Unload if resident</td>
</tr>
<tr>
<td>/c</td>
<td>Close listen</td>
</tr>
<tr>
<td>/d</td>
<td>Do not start remote console</td>
</tr>
<tr>
<td>/g</td>
<td>Allow old type (spawning) CGI</td>
</tr>
<tr>
<td>/p</td>
<td>Passive mode</td>
</tr>
<tr>
<td>/i=&lt;InterruptNumber&gt;</td>
<td>Interrupt number for cgi API</td>
</tr>
<tr>
<td>/m=&lt;MemorySize&gt;</td>
<td>Set memory size</td>
</tr>
<tr>
<td>/n=&lt;MaximumConnections&gt;</td>
<td>Number of simultaneous connections</td>
</tr>
<tr>
<td>/a=&lt;ScreenX&gt;, &lt;ScreenY&gt;</td>
<td>Set screen aspect</td>
</tr>
<tr>
<td>/v=&lt;ScreenBufferSegment&gt;[; ScreenBufferOffset&gt;]</td>
<td>Set video buffer address (hex)</td>
</tr>
<tr>
<td>/k</td>
<td>Unload and abort all active connections</td>
</tr>
</tbody>
</table>

Remarks

**ScreenX**, **ScreenY**

The width and height of the screen area to serve for the remote console session. These values default to 80 and 25, respectively.

**ScreenBufferSegment**, **ScreenBufferOffset**

Together, a pointer to the top-left corner of the display memory to serve for the remote console session. These values default to B000 and 0000 respectively, for monochrome display adapters and to B800 and 0000 respectively, for color display adapters.

**MemorySize**

The maximum amount of memory available to the server. The default value is 32K. The value of m can range from 8192 to 63472.

**MaximumConnections**

The maximum number of simultaneous connections allowed by the server.
Chapter 7 HTTP and FTP Server Application

InterruptNumber
The interrupt number to access the CGI API.

http_port
HTTP port to listen on. This parameter defaults to the standard HTTP port number of 80.

rc_port
Remote Console port to listen on. This parameter defaults to 81.

The "root" directory for web content is the current directory when HTTPD is started. This can be changed by setting an environment variable HTTP_DIR e.g.

SET HTTP_DIR=D:\SERVER\WEB

Format of "SOCKET.UPW"
This is the same file used for the HTTP and FTP server’s (FTPD.EXE) permissions. This file consists of lines where each line contains a user’s information. A line starting with a # is considered a comment and is ignored. Each line consists of four fields:

<Username> <Password> <Working Directory> <Permissions> [# comment]

® Username: The name of this user. If it is *, it will be used when the client does not specify a username.

® Password: This user’s password. If it is *, no password is required

® Working Directory: The user will only have access to this directory and its subdirectories. If it is /", this user has access to the whole system. HTTP_DIR can be referred to as ‘\’. If a relative path is specified, it is appended to HTTP_DIR.

® Permissions: When a user is granted both FTP and HTTP permissions, the FTP permissions must appear first, otherwise they will be ignored. Permission are listed below:

FTP Rights:
  d  change directories
  c  create/delete directories
  w  write files
Chapter 7 HTTP and FTP Server Application

read files
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HTTP Rights:
- e  get files
- p  post files
- g  use CGI
- m  use remote console

Fields should be separated by single spaces. If any field is missing the entry is ignored. A comment may follow the last field (permissions) of the line.

Format of "htaccess"

Any directory may contain this file, and serve as overrides to the general permissions for the containing directory and all its subs until another htaccess is found. This file consists of lines where each line contains a user's information. A line starting with a # is considered a comment and is ignored. Each line consists of three fields:

<Username> <Password> <Permissions> [# comment]

- Username: The name of this user. If it is *, it will be used when the client does not specify a username.
- Password: This user's password. If it is *, no password is required
- Permissions: Operations allowed. Permission are listed below:
  - e  - User may 'get' files
  - p  - User may 'post' files
  - g  - User may use CGI

Fields should be separated by single spaces. If any field is missing the entry is ignored. A comment may follow the last field (permissions) of the line.

Note: If a default user is supplied, it should always appear first in the list of users. Only users below the default user will be considered.
FTP Server

**FTPD** is a file server that can run either as an application or as a TSR. The name of the server as displayed in the banner is determined by the **HOSTNAME** environment variable. If the environment variable is not set, the name “Socket” is used. The user password file, **SOCKET.UPW**, in the **SOCKETS** directory (indicated by the **SOCKETS** environment variable) controls access.

A temporary file is created when a directory listing is requested. This file is created in the current directory, but can be created in any directory as specified in the **FTPDIR** environment variable.

FTP Server Application

**FTP D Program**

The syntax for FTPD is:

```
FTPD [options] [<ftp_port>]
```

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>/?</td>
<td>Display help screen</td>
</tr>
<tr>
<td>/h</td>
<td>Run server in TSR mode</td>
</tr>
<tr>
<td>/r</td>
<td>Display server status</td>
</tr>
<tr>
<td>/u</td>
<td>Unload if resident</td>
</tr>
<tr>
<td>/c</td>
<td>Close listen</td>
</tr>
<tr>
<td>/m=&lt;MemorySize&gt;</td>
<td>Set memory size</td>
</tr>
<tr>
<td>/n=&lt;MaximumConnections&gt;</td>
<td>Number of simultaneous connections</td>
</tr>
<tr>
<td>/k</td>
<td>Abort all active connections and unload</td>
</tr>
</tbody>
</table>

Remarks

*MemorySize*

The number of bytes of memory available to the server. This value defaults to 32768.

*MaximumConnections*

The maximum number of simultaneous connections allowed by the server.

*ftp_port*

FTPD will listen on the listed port. This parameter defaults to the standard FTP port number of 21.
Configuration File

FTPD uses the standard SOCKET.UPW file for validating logins. The file is composed of text lines, each representing a login name, password, and the configuration to use for a session opened with those credentials. Space characters separate the parameters in the file, which are in the following format:

name password directory rights

The location of the username/password file to be used by the server is specified by the environment variable SOCKETS as follows:
%SOCKETS%\SOCKET.UPW

If the variable SOCKETS is not specified, the following file is used:
\DL\SOCKETS\SOCKET.UPW

Configuration File Parameters

ame
The login name of this record.

password
The password to authenticate a user trying to login as this name.

directory
The starting directory for this user.

rights
Up to four characters specifying which permissions this user is granted:
r means that this user has read access.
w means that this user has write access.
c means that this user has permission to make new directories.
d means that this user has permission to change to a directory other than his starting location and subdirectories from the starting location.

Example Socket.upw
Admin admin c:\ drwc
Guest * c:\guest dr

Example Command Line
FTPD /m=40000 /r
### Chapter 7 HTTP and FTP Server Application

#### FTP Server Commands

The following commands are recognised by the SOCKETS FTP server:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Abort</td>
<td>cancel an incomplete transfer</td>
</tr>
<tr>
<td>append</td>
<td>&quot;put&quot; a file at the server but append it if the file exists</td>
</tr>
<tr>
<td>cwd directory</td>
<td>change server directory</td>
</tr>
<tr>
<td>dele file</td>
<td>delete a server file</td>
</tr>
<tr>
<td>list [file</td>
<td>directory]</td>
</tr>
<tr>
<td>mkd remote_directory</td>
<td>create a server directory</td>
</tr>
<tr>
<td>nlst [file</td>
<td>directory]</td>
</tr>
<tr>
<td>pass [password]</td>
<td>password for username</td>
</tr>
<tr>
<td>pasv [on</td>
<td>off]</td>
</tr>
<tr>
<td>retr remote_file</td>
<td>transfer a file from the server in the current mode</td>
</tr>
<tr>
<td>stor local_file</td>
<td>transfer a file to the server in the current mode</td>
</tr>
<tr>
<td>pwd</td>
<td>print working directory</td>
</tr>
<tr>
<td>quit</td>
<td>terminate FTP session</td>
</tr>
<tr>
<td>rmd remote_directory</td>
<td>remove (delete) directory</td>
</tr>
<tr>
<td>rnfr existing_filename</td>
<td>rename a file, command 1 of</td>
</tr>
<tr>
<td>2 rnto new_filename</td>
<td>rename a file, command 2 of</td>
</tr>
<tr>
<td>2 site [path I nopath]</td>
<td>use full path description</td>
</tr>
<tr>
<td>site raw [interface]</td>
<td>open a session to a raw host using one of the raw lines (interfaces) specified</td>
</tr>
<tr>
<td>site sub-command</td>
<td>command to be passed on to raw host</td>
</tr>
<tr>
<td>size file</td>
<td>report the file size in bytes as a message prefixed with 213</td>
</tr>
<tr>
<td>stat</td>
<td>report the status of a transfer or active connections</td>
</tr>
<tr>
<td>system</td>
<td>return operating system information from the server</td>
</tr>
<tr>
<td>type [i I a]</td>
<td>report or select the file transfer mode image (binary) or ASCII</td>
</tr>
<tr>
<td>user [username]</td>
<td>username to logon</td>
</tr>
</tbody>
</table>
Combined HTTP and FTP Server

HTTPFTPD is a combined HTTP and FTP server that can run either as an application or as a TSR. By default, it processes normal HTTP requests on port 80 and normal FTP requests on port 21. It also serves a proprietary session displaying the contents of text-mode display memory to the RC.JAR and RCCLI client applications. This feature is commonly called the “remote console.” If the HTTPFTPD server is loaded as a DOS TSR program, set the environment variable, HTTP_DIR, to the location of the INDEX.HTML file; for example, SET HTTP_DIR=C:\DL\SOCKETS\SERVER

HTTPFTPD Program

The syntax for FTTPD is:

HTTPFTPD [options] [<http_port> [<ftp_port> [<rc_port>]]]

Any combination of these switches may be used. They should be separated by at least one space.

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>/? /h</td>
<td>Display help screen</td>
</tr>
<tr>
<td>/r</td>
<td>Run server in TSR mode</td>
</tr>
<tr>
<td>/s</td>
<td>Display server status</td>
</tr>
<tr>
<td>/t</td>
<td>Enable htaccess directory level authentication</td>
</tr>
<tr>
<td>/u</td>
<td>Unload if resident</td>
</tr>
<tr>
<td>/c</td>
<td>Close listen</td>
</tr>
<tr>
<td>/d</td>
<td>Do not start remote console</td>
</tr>
<tr>
<td>/g</td>
<td>Allow old type (spawning) CGI</td>
</tr>
<tr>
<td>/p</td>
<td>Passive mode</td>
</tr>
<tr>
<td>/i=&lt;&lt;InterruptNumber&gt;</td>
<td>Interrupt number for cgi API</td>
</tr>
<tr>
<td>/m=&lt;&lt;MemorySize&gt;</td>
<td>set memory size</td>
</tr>
<tr>
<td>/n=&lt;&lt;MaximumConnections&gt;</td>
<td>number of simultaneous connections</td>
</tr>
<tr>
<td>/a=&lt;&lt;ScreenX&gt;, &lt;ScreenY&gt;</td>
<td>set screen aspec</td>
</tr>
<tr>
<td>/v=&lt;&lt;ScreenBufferSegment&gt;[&lt;ScreenBufferOffset&gt;]</td>
<td>set video buffer address (hex)</td>
</tr>
<tr>
<td>/k</td>
<td>Abort all active connections and unload</td>
</tr>
</tbody>
</table>

Remarks

**ScreenX, ScreenY**

The width and height of the screen area to serve for the remote console session. These values default to 80 and 25, respectively.
Chapter 7 HTTP and FTP Server Application

ScreenBufferSegment, ScreenBufferOffset
Together, a pointer to the top-left corner of the display memory to serve for the remote console session. These values default to B000 and 0000 respectively, for monochrome display adapters and to B800 and 0000 respectively, for color display adapters.

MemorySize
The maximum amount of memory available to the server. The default value is 32K. The value of \( m \) can range from 8192 to 63472.

MaximumConnections
The maximum number of simultaneous connections allowed by the server.

InterruptNumber
The interrupt number to access the CGI API.

http_port
HTTP port to listen on. This parameter defaults to the standard HTTP port number of 80.

ftp_port
FTP port to listen on. This parameter defaults to the standard FTP port number of 21

rc_port
Remote Console port to listen on. This parameter defaults to 81.

Configuration File

HTTPFTPD uses the standard SOCKET.UPW file for validating logins. The file is composed of text lines, each representing a login name, password, and the configuration to use for a session opened with those credentials.

Space characters separate the parameters in the file, which are in the following format:

name password directory rights

The location of the username/password file to be used by the server is specified by the environment variable SOCKETS as follows:

%SOCKETS%\SOCKET.UPW

If the variable SOCKETS is not specified, the following file is used:

\DL\SOCKETS\SOCKET.UPW
Chapter 7 HTTP and FTP Server Application

Configuration File Parameters

name
The login name of this record.

password
The password to authenticate a user trying to login as this name.

directory
The starting directory for this user.

w means that this user has write access.
c means that this user has permission to make new directories.
d means that this user has permission to change to a directory other than his starting location and subdirectories from the starting location.
e means that this user may 'get' files
p means that this user may 'post' files
g means that this user may use cgi
m means that this user may use Remote Console

Example Command Lines

HTTPFTPD /m=40000
HTTPFTPD /a=80,25 /v=a000:0000
This appendix gives a short description of each module’s registers. For more information, please refer to the STARTECH 16C550 UART chip data book. All registers are one byte. Bit 0 is the least significant bit, and bit 7 is the most significant bit. The address of each register is specified as an offset from the port base address (BASE), COM1 is 3F8h and COM2 is 2F8h.

DLAB is the “Divisor Latch Access Bit”, bit 7 of BASE+3.

BASE+0 Receiver buffer register when DLAB=0 and the operation is a read.
BASE+0 Transmitter holding register when DLAB=0 and the operation is write.
BASE+0 Divisor latch bits 0 - 7 when DLAB=1
BASE+1 Divisor latch bits 8-15 when DLAB=1.

Bytes BASE+0 and BASE+1 together form a 16-bit number, the divisor, which determines the baud rate. Set the divisor as follows:

<table>
<thead>
<tr>
<th>Baud rate</th>
<th>Divisor</th>
<th>Baud rate</th>
<th>Divisor</th>
</tr>
</thead>
<tbody>
<tr>
<td>50</td>
<td>2304</td>
<td>2400</td>
<td>48</td>
</tr>
<tr>
<td>75</td>
<td>1536</td>
<td>3600</td>
<td>32</td>
</tr>
<tr>
<td>110</td>
<td>1047</td>
<td>4800</td>
<td>24</td>
</tr>
<tr>
<td>133.5</td>
<td>857</td>
<td>7200</td>
<td>16</td>
</tr>
<tr>
<td>150</td>
<td>768</td>
<td>9600</td>
<td>12</td>
</tr>
<tr>
<td>300</td>
<td>384</td>
<td>19200</td>
<td>6</td>
</tr>
<tr>
<td>600</td>
<td>192</td>
<td>38400</td>
<td>3</td>
</tr>
<tr>
<td>1200</td>
<td>96</td>
<td>56000</td>
<td>2</td>
</tr>
<tr>
<td>1800</td>
<td>64</td>
<td>115200</td>
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</tr>
<tr>
<td>2000</td>
<td>58</td>
<td>x</td>
<td>x</td>
</tr>
</tbody>
</table>
Appendix A COM Port Register Structure

BASE+1 Interrupt Status Register (ISR) when DLAB=0
bit 0: Enable received-data-available interrupt
bit 1: Enable transmitter-holding-register-empty interrupt
bit 2: Enable receiver-line-status interrupt
bit 3: Enable modem-status interrupt

BASE+2 FIFO Control Register (FCR)
bit 0: Enable transmit and receive FIFOs
bit 1: Clear contents of receive FIFO
bit 2: Clear contents of transmit FIFO
bits 6-7: Set trigger level for receiver FIFO interrupt

<table>
<thead>
<tr>
<th>Bit 7</th>
<th>Bit 6</th>
<th>FIFO trigger level</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>01</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>04</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>08</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>14</td>
</tr>
</tbody>
</table>

BASE+3 Line Control Register (LCR)
bit 0: Word length select bit 0
bit 1: Word length select bit 1

<table>
<thead>
<tr>
<th>Bit 1</th>
<th>Bit 0</th>
<th>Word length (bits)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
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<td>5</td>
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<tr>
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<td>0</td>
<td>7</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>8</td>
</tr>
</tbody>
</table>
Appendix A COM Port Register Structure

BASE+4   Modem Control Register (MCR)
bit 0: DTR
bit 1: RTS

BASE+5   Line Status Register (LSR)
bit 0: Receiver data ready
bit 1: Overrun error
bit 2: Parity error
bit 3: Framing error
bit 4: Break interrupt
bit 5: Transmitter holding register empty
bit 6: Transmitter shift register empty
bit 7: At least one parity error, framing error or break indication in the FIFO

BASE+6   Modem Status Register (MSR)
bit 0: Delta CTS
bit 1: Delta DSR
bit 2: Trailing edge ring indicator
bit 3: Delta received line signal detect
bit 4: CTS
bit 5: DSR
bit 6: RI
bit 7: Received line signal detect

BASE+7   Temporary data register
Appendix B
RS-485 Network
EIA RS-485 is the industry’s most widely used bidirectional, balanced transmission line standard. It is specifically developed for industrial multi-drop systems that should be able to transmit and receive data at high rates or over long distances.

The specifications of the EIA RS-485 protocol are as follows:

- Maximum line length per segment: 1200 meters (4000 feet)
- Throughput of 10M baud and beyond - Differential transmission (balanced lines) with high resistance against noise
- Maximum 32 nodes per segment
- Bi-directional master-slave communication over a single set of twisted-pair cables
- Parallel connected nodes, true multi-drop

ADAM-4500 Series Controller is fully isolated and use just a single set of twisted pair wires to send and receive! Since the nodes are connected in parallel they can be freely disconnected from the host without affecting the functioning of the remaining nodes. An industry standard, shielded twisted pair is preferable due to the high noise ratio of the environment. When nodes communicate through the network, no sending conflicts can occur since a simple command/response sequence is used. There is always one initiator (with no address) and many slaves (with addresses). In this case, the master is a personal computer that is connected with its serial, RS-232, port to an ADAM RS-232/RS-485 converter. The slaves are the ADAM-4500 Series Controller. When systems are not transmitting data, they are in listen mode. The host computer initiates a command/response sequence with one of the systems. Commands normally contain the address of the module the host wants to communicate with. The system with the matching address carries out the command and sends its response to the host.
Appendix B RS-485 Network

B.1 Basic Network Layout

Multi-drop RS-485 implies that there are two main wires in a segment. The connected systems tap from these two lines with so called drop cables. Thus all connections are parallel and connecting or disconnecting of a node doesn’t affect the network as a whole. Since ADAM-4500 Series Controller use the RS-485 standard, they can connect and communicate with the host PC. The basic layouts that can be used for an RS-485 network are:

Daisychain
The last module of a segment is a repeater. It is directly connected to the main-wires thereby ending the first segment and starting the next segment. Up to 32 addressable systems can be daisychained. This limitation is a physical one. When using more systems per segment the IC driver current rapidly decreases, causing communication errors. In total, the network can hold up to 64 addressable systems. The limitation on this number is the two-character hexadecimal address code that can address 64 combinations. The ADAM converter, ADAM repeaters and the host computer are non addressable units and therefore are not included in these numbers.

Figure B-1: Daisychaining
Star Layout
In this scheme the repeaters are connected to drop-down cables from the main wires of the first segment. A tree structure is the result. This scheme is not recommended when using long lines since it will cause a serious amount of signal distortion due to signal reflections in several line-endings.

![Star structure diagram]

Figure B-2: Star structure

Random
This is a combination of daisychain and hierarchical structure.

![Random structure diagram]

Figure B-3: Random structure
Appendix B RS-485 Network

B.2 Line Termination

Each discontinuity in impedance causes reflections and distortion. When an impedance discontinuity occurs in the transmission line the immediate effect is signal reflection. This will lead to signal distortion. Especially at line ends this mismatch causes problems. To eliminate this discontinuity, terminate the line with a resistor.

![Figure B-4: Signal distortion](image)

The value of the resistor should be as close as possible to the characteristic impedance of the line. Although receiver devices add some resistance to the whole of the transmission line, normally it is sufficient if the resistor impedance should equal the characteristic impedance of the line.

Example: Each input of the receivers has a nominal input impedance of 18 k Ω feeding into a diode transistor- resistor biasing network that is equivalent to an 18 input resistor tied to a common mode voltage of 2.4 V. It is this configuration, which provides the large common range of the receiver required for RS-485 systems!
Because each input is biased to 2.4 V, the nominal common mode voltage of balanced RS-485 systems, the 18 k on the input can be taken as being in series across the input of each individual receiver. If thirty of these receivers are put closely together at the end of the transmission line, they will tend to react as thirty 36k resistors in parallel with the termination resistor. The overall effective resistance will need to be close to the characteristics of the line. The effective parallel receiver resistance \( R_P \) will therefore be equal to:

\[
R_P = 36 \times 10^3/30 = 1200 \Omega
\]

While the termination receptor \( R_T \) will equal:

\[
R_T = R_D / [1 - R_D/R_P]
\]

Thus for a line with a characteristic impedance of 100 resistor \( R_T = 100/[1 - 100/1200] = 110 \Omega \)

Since this value lies within 10% of the line characteristic impedance.
Appendix B RS-485 Network

Thus as already stated above the line termination resistor $R_T$ will normally equal the characteristic impedance $Z_0$. The star connection causes a multitude of these discontinuities since there are several transmission lines and is therefore not recommend.

Note: The recommend method wiring method, that causes a minimum amount of reflection, is daisy chaining where all receivers tapped from one transmission line needs only to be terminated twice.

B.3 RS-485 Data Flow Control

The RS-485 standard uses a single pair of wires to send and receive data. This line sharing requires some method to control the direction of the data flow. RTS (Request To Send) and CTS (Clear To Send) are the most commonly used methods.

![Figure B-6: RS-485 data flow control with RTS](image)

Intelligent RS-485 Control

ADAM-4510 and ADAM-4520 are both equipped with an I/O circuit which can automatically sense the direction of the data flow. No handshaking with the host (like RTS, Request to Send) is necessary to receive data and forward it in the correct direction. You can use any software written for half-duplex RS-232 with an ADAM network without modification. The RS-485 control is completely transparent to the user.
Field Grounding and Shielding Application

Overview

Unfortunately, it's impossible to finish a system integration task at one time. We always meet some trouble in the field. A communication network or system isn’t stable, induced noise or equipment is damaged or there are storms. However, the most usual issue is just simply improper wiring, ie, grounding and shielding. You know the 80/20 rule in our life: we spend 20% time for 80% work, but 80% time for the last 20% of the work. So is it with system integration: we pay 20% for Wire / Cable and 0% for Equipment. However, 80% of reliability depends on Grounding and Shielding. In other words, we need to invest more in that 20% and work on these two issues to make a highly reliable system. This application note brings you some concepts about field grounding and shielding. These topics will be illustrated in the following pages.

1. Grounding
   1.1 The ‘Earth’ for reference
   1.2 The ‘Frame Ground’ and ‘Grounding Bar’
   1.3 Normal Mode and Common Mode
   1.4 Wire impedance
   1.5 Single Point Grounding

2. Shielding
   2.1 Cable Shield
   2.2 System Shielding

3. Noise Reduction Techniques

4. Check Point List
C.1 Grounding

C-1.1 The ‘Earth’ for reference

As you know, the EARTH cannot be conductive. However, all buildings lie on, or in, the EARTH. Steel, concrete and associated cables (such as lighting arresters) and power system were connected to EARTH. Think of them as resistors. All of those infinite parallel resistors make the EARTH as a single reference point.
C-1.2 The ‘Frame Ground’ and ‘Grounding Bar’

Grounding is one of the most important issues for our system. Just like Frame Ground of the computer, this signal offers a reference point of the electronic circuit inside the computer. If we want to communicate with this computer, both Signal Ground and Frame Ground should be connected to make a reference point of each other's electronic circuit. Generally speaking, it is necessary to install an individual grounding bar for each system, such as computer networks, power systems, telecommunication networks, etc. Those individual grounding bars not only provide the individual reference point, but also make the earth our ground!

Neutral is the physical cable from Generator. Ground is the local physical cable that connected to Ground Bar.

Figure C-2: Grounding Bar.
C-1.3 Normal Mode and Common Mode

Have you ever tried to measure the voltage between a live circuit and a concrete floor? How about the voltage between neutral and a concrete floor? You will get nonsense values. ‘Hot’ and ‘Neutral’ are just relational signals: you will get 110VAC or 220VAC by measuring these signals. Normal mode and common mode just show you that the Frame Ground is the most important reference signal for all the systems and equipments.
**Figure C-4: Normal mode and Common mode.**

- Ground-pin is longer than others, for first contact to power system and noise bypass.
- Neutral-pin is broader than Live-pin, for reducing contact impedance.
C-1.4 Wire impedance

- What's the purpose of high voltage transmission? We have all seen high voltage transmission towers. The power plant raises the voltage while generating the power, then a local power station steps down the voltage. What is the purpose of high voltage transmission wires? According to the energy formula, \( P = V \times I \), the current is reduced when the voltage is raised. As you know, each cable has impedance because of the metal it is made of. Referring to Ohm's Law, \( V = I \times R \) this decreased current means lower power losses in the wire. So, high voltage lines are for reducing the cost of moving electrical power from one place to another.

![Wire Impedance](image)

*Figure C-6: The wire impedance will consume the power.*
C-1.5 Single Point Grounding

What's Single Point Grounding? Maybe you have had an unpleasant experience while taking a hot shower in winter. Someone turns on a hot water faucet somewhere else. You will be impressed with the cold water! The bottom diagram above shows an example of how devices will influence each other with swift load change. For example, normally we turn on all the four hydrants for testing. When you close the hydrant 3 and hydrant 4, the other two hydrants will get more flow. In other words, the hydrant cannot keep a constant flow rate.

Figure C-7: Single point grounding. (1)
The above diagram shows you that a single point grounding system will be a more stable system. If you use thin cable for powering these devices, the end device will actually get lower power. The thin cable will consume the energy.
C.2 Shielding

C-2.1 Cable Shield

The diagram shows the structure of an isolated cable. You see the insulated layer which is spiraled Aluminum foil to cover the wires. This spiraled structure makes a layer for shielding the cables from external noise.

Figure C-9: Single isolated cable

- Single isolated cable

Use Aluminum foil to cover those wires, for isolating the external noise.
Double isolated cable

Figure 10 is an example of a double isolated cable. The first isolating layer of spiraled aluminum foil covers the conductors. The second isolation layer is several bare conductors that spiral and cross over the first shield layer. This spiraled structure makes an isolated layer for reducing external noise. Additionally, follow these tips just for your reference.

- The shield of a cable cannot be used for signal ground. The shield is designed for carrying noise, so the environment noise will couple and interfere with your system when you use the shield as signal ground.
- The higher the density of the shield - the better, especially for communication network.
- Use double isolated cable for communication network / AI / AO.
- Both sides of shields should be connected to their frame while inside the device. (for EMI consideration)
- Don’t strip off too long of plastic cover for soldering.

Figure C-10: Double isolated cable
Appendix C Grounding Reference

C-2.2 System Shielding

Figure C-11: System Shielding

- Never stripping too long of the plastic cable cover. This is improper and can destroy the characteristics of the Shielded-Twisted-Pair cable. Besides, the bare wire shield easily conducts the noise.
- Cascade these shields together by soldering. Please refer to following page for further detailed explanation.
- Connect the shield to Frame Ground of DC power supply to force the conducted noise to flow to the frame ground of the DC power supply. (The ‘frame ground’ of the DC power supply should be connected to the system ground)

C-12 ADAM-4500 Series User’s Manual
• The characteristic of the cable
  Don’t strip off too much insulation for soldering. This could change the effectiveness of the Shielded-Twisted-Pair cable and open a path to introduce unwanted noise.
Figure C-13: System Shielding (1)

• Shield connection (1)
  If you break into a cable, you might get in a hurry to achieve your goal. As in all electronic circuits, a signal will use the path of least resistance. If we make a poor connection between these two cables we will make a poor path for the signal. The noise will try to find another path for easier flow.
System Shielding

Figure C-14: System Shielding (2)

• Shield connection (2)

The previous diagram shows you that the fill soldering just makes an easier way for the signal.
Appendix C Grounding Reference

C.3 Noise Reduction Techniques

- Isolate noise sources in shielded enclosures.
- Place sensitive equipment in shielded enclosure and away from computer equipment.
- Use separate grounds between noise sources and signals.
- Keep ground/signal leads as short as possible.
- Use Twisted and Shielded signal leads.
- Ground shields on one end ONLY while the reference grounds are not the same.
- Check for stability in communication lines.
- Add another Grounding Bar if necessary.
- The diameter of power cable must be over 2.0 mm².
- Independent grounding is needed for A/I, A/O, and communication network while using a jumper box.
- Use noise reduction filters if necessary. (TVS, etc)
- You can also refer to FIPS 94 Standard. FIPS 94 recommends that the computer system should be placed closer to its power source to eliminate load-induced common mode noise.

Figure C-15: Noise Reduction Techniques
C.4 Check Point List

- Follow the single point grounding rule?
- Normal mode and common mode voltage?
- Separate the DC and AC ground?
- Reject the noise factor?
- The shield is connected correctly?
- Wire size is correct?
- Soldered connections are good?
- The terminal screw are tight?