**Movement**

- Move: movement command for all axes
- MoveOvl: movement command with asynchronous axis movement
- MoveAxis: movement command for one axis
- MoveCirc: Cartesian movement command with circular path interpolation
- MoveUntil: Move the robot to the target position only when the digital input is true.
- StopRobot: stops the robot program immediately. Press the "Start" button again to restart the program.
- Palletize: Moves the robot to the next free place position on a pallet.
- AfterPalletize: Moves the robot to the current pick position

**Homing**

- RefRobotAxis: Reference axis position.
- RefRobotAxisAsync: reference axis asynchronously.
- WaitRefFinished: wait until all the reference points are set.

**Settings**

- Dynamic: Sets the maximum velocity, acceleration, and deceleration for subsequent robot motions.
- DynamicAxis: Sets the maximum velocity, acceleration, and deceleration for subsequent robot motions only for one axis.
- Increment: Increments the double integer variable.
- Decrement: Decrements the double integer variable.
- ResetPallet: Sets the pallet counter to the given value
- SoftTorqueON: Makes an axis "Soft" by reducing the actual torque that is used to hold the axis in position.
- SoftTorqueOff: Disables the soft torque feature for the specified axis

**I/O Control**

- Gripper:
- GripperGroup: Issues the OPEN or CLOSE command to a gripper group
- Vacuum:
- VacuumGroup: Issues the OPEN or CLOSE command to a vacuum group.
- ObservelMMIO:
- CheckHomePos: checking the home position
- IMMIOActionAddToQueue:
- IMMIOActionQueueSet:
- IMMIOActionQueueClear:
- IMMStartup: Prepares the injection molding machine.
- SetDO: Sets or clears a digital output.
- PulseDO:
- SetIMM: Sets or clears EUROMAP signals

**Flow control**

- Assignment: Assigns a value to a variable
- Comment: Adds a comment to the code which is ignored by the compiler.
- IF: IF true -> do this…
- ELSE: ELSE-> do that
- WHILE: While true-> do this constantly.
- RUN: Executes a second program within anther thread of execution
- KILL: Terminates the execution of another program.

**Timing**

- WaitTimeSec: Wait for the specified amount of time before the program continues.
- WaitDIN: Pause the program main run until a digital input has a rising edge.
- OnParameter: Trigger condition is met
- WaitIMM: wait for the specified EUROMAP signal
- WAIT: wait until <CONDITION> is true.

**HanYang**

- DeclareRobotUnreferenced : clear the reference point for an axis.
- HYHoming: Robot will move to origin.
- HYMainRelease: Device will release the mold
- HYMove: Robot will move to a specific position.
- HYRotation: Rotate pneumatic device.
- HYRotationReturn: Return rotated pneumatic device.
- HYRunnerRelease: release the sub arm.
- HYRunnerReturnRelease: return released sub arm.
- HYSenDI: send digital input.
- HYStartUp: set digital output to turn on or off the temperature and weight sensor. . Make IMM ready for auto mode.
- HYSwivel: Swivel pneumatic device
- HYSwivelReturn: Return swiveled pneumatic device
- HYTakeOutPosition: Take out the robot from IMM
- HYToWaitingPos: going back to waiting position. Wait for IMM to finish.
- HYUpPosition: Move up.
- HYVacuumOFF: Vacuum OFF

- HYVacuumON: Vacuum ON
- HYWaitForIMM: wait for IMM to finish its working before continuing.
- HYWaitMovelsFinished: wait for entire move to finish before going to the next move (command).
- RefRobotAxisHY: Re-reference the selected axis.