



SMC_ERROR (ENUM) SMC_ERROR (枚举)

TYPE SMC_ERROR :

The enumeration **SMC_ERROR** contains all error numbers that can be returned by SoftMotion function blocks. [SMC_ErrorString](#) generates an error string output.

枚举 **SMC_ERROR** 包含了 SoftMotion 函数块可以返回的所有错误编号。SMC_ErrorString 生成错误字符串输出。

InOut:

Name 名称	Initial 初始	Comment 注释
SMC_NO_ERROR	0	No error 无错误
SMC_DI_GENERAL_COMMUNICATION_ERROR	1	Communication error. The fieldbus slave is no longer in state operational. 通信错误。现场总线从站不再处于运行状态。
SMC_DI_AXIS_ERROR	2	Axis error 轴错误
SMC_DI_FIELDBUS_LOST_SYNCHRONICITY	3	Fieldbus has lost synchronicity 现场总线失去同步性
SMC_DI_SWLIMITS_EXCEEDED	10	Position outside of permissible range of SWLimit 位置超出 SWLimit 的可接受范围
SMC_DI_HWLIMITS_EXCEEDED	11	Hardware end switch is active 硬件端限位开关处于激活状态

Name 名称	Initial 初始	Comment 注释
SMC_DI_LINEAR_AXIS_OVERFLOW	12	This error occurs if a linear axis has more than 2^15 32-bit overflows of the position in increments 如果线性轴的位置在增量上有超过 2^15 个 32 位溢出，则会出现此错误
SMC_DI_HALT_OR_QUICKSTOP_NOT_SUPPORTED	13	Drive status Halt or Quickstop is not supported 驱动状态 Halt 或 Quickstop 不受支持
SMC_DI_VOLTAGE_DISABLED	14	Drive has no power 驱动器无电源
SMC_DI_IRREGULAR_POSITION	15	This error is no longer used 此错误不再使用
SMC_DI_POSITION_LAG_ERROR	16	Position lag error. Difference between set and current position exceeds the given limit 位置滞后错误。设置位置与当前位置之间的差值超过给定限制
SMC_DI_HOMING_ERROR	17	Homing error reported by axis 轴报告的归家错误
SMC_DI_LICENSE_ERROR	18	A problem with the license occurred 许可证出现问题
SMC_DI_DRIVE_LIMIT_ACTIVE	19	A limit of the drive is active, for example an i²t error has occurred. 驱动器存在限制，例如发生了 i²t 错误。
SMC_REGULATOR_OR_START_NOT_SET	20	Controller enable not done or brake applied 控制器未启用或已应用制动
SMC_WRONG_CONTROLLER_MODE	21	Axis in wrong controller mode 轴处于错误的控制器模式
SMC_INVALID_ACTION_FOR_LOGICAL	25	Invalid action at logical axis 逻辑轴上的无效操作

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_IS_NOT_OPERATIONAL	27	Axis is not operational <code>wCommunicationState <> 100</code> 轴在 <code>wCommunicationState <> 100</code> 处未运行
SMC_AXIS_NOT_FOLLOWING_SETVALUES	28	Axis is currently not following the set values 轴当前未按设定值运行
SMC_FB_WAS_NOT_CALLED_DURING_MOTION	30	Motion creating module has not been called again before end of the motion 运动创建模块在运动结束前未被再次调用
SMC_AXIS_IS_NO_AXIS_REF	31	Type of given <code>AXIS_REF</code> variable is not <code>AXIS_REF</code> 给定的 <code>AXIS_REF</code> 变量的类型不是 <code>AXIS_REF</code>
SMC_AXIS_REF_CHANGED_DURING_OPERATION	32	<code>AXIS_REF</code> variable has been exchanged while the module was active. <code>AXIS_REF</code> 变量在模块激活时已被交换。
SMC_FB_ACTIVE_AXIS_DISABLED	33	Axis disabled while being moved. <code>MC_Power.bRegulatorOn</code> 在移动时轴已禁用。 <code>MC_Power.bRegulatorOn</code>
SMC_AXIS_NOT_READY_FOR_MOTION	34	Axis in its current state cannot execute a motion command, because the axis doesn't signal currently that it follows the target values. 当前状态下轴无法执行运动命令，因为轴目前没有发出它正在跟随目标值的信号。
SMC_AXIS_ERROR_DURING_MOTION	35	The drive reported an error during an ongoing movement. 驱动器在持续运动过程中报告了错误。
SMC_FB_CALLED_FROM_WRONG_TASK	36	The function block was called from the wrong task. 该功能块是从错误的任务中调用的。

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SMC_INVALID_DISTRIBUTE_CLOCKS_SETTINGS	37	<p>The distributed clock settings of the EtherCAT slave are invalid. If both SYNC0 and SYNC1 are enabled, we expect that the SYNC0 cycle time is not greater than the SYNC1 cycle time, and that the SYNC1 cycle time is an integer multiple of the SYNC0 cycle time.</p> <p>EtherCAT 从站的分布式时钟设置无效。如果 SYNC0 和 SYNC1 都被启用，我们期望 SYNC0 周期时间不大于 SYNC1 周期时间，并且 SYNC1 周期时间是 SYNC0 周期时间的整数倍。</p>
SMC_INVALID_TIMESTAMP	38	<p>The timestamp is invalid, no actual position is available for SMC_ETC_InterpolateAxisPosition. Check whether the library parameter LibParams.gc_SMC_ACT_VALUE_BUFFER_SIZE_BASE2_EXP is sufficiently large.</p> <p>时间戳无效，SMC_ETC_InterpolateAxisPosition 没有实际位置可用。检查库参数 LibParams.gc_SMC_ACT_VALUE_BUFFER_SIZE_BASE2_EXP 是否足够大。</p>
SMC_AXIS_ERROR_DUE_TO_FB_ERROR	39	<p>Axis error due to a severe FB error in the active motion function block.</p> <p>由于主动运动功能块中发生严重的 FB 错误，导致轴错误。</p>
SMC_VD_MAX_VELOCITY_EXCEEDED	40	<p>Maximum velocity fMaxVelocity exceeded</p> <p>fMaxVelocity 最大速度超出</p>
SMC_VD_MAX_ACCELERATION_EXCEEDED	41	<p>Maximum acceleration fMaxAcceleration exceeded</p> <p>fMaxAcceleration 最大加速度超出</p>
SMC_VD_MAX_DECELERATION_EXCEEDED	42	<p>Maximum deceleration fMaxDeceleration exceeded</p> <p>fMaxDeceleration 最大减速度超出</p>
SMC_3SH_INVALID_VELOCITY_VALUES	50	<p>Invalid velocity, acceleration, deceleration, or jerk values</p> <p>无效的速度、加速度、减速度或加加速度值</p>
SMC_3SH_MODE_NEEDS_HWLIMIT	51	<p>Mode requests for safety reasons use of end switches.</p> <p>出于安全原因，模式请求使用限位开关。</p>
SMC_FRC_NO_FREE_HANDLE	60	<p>No free handle has been sent to open file.</p> <p>未发送空闲手柄来打开文件。</p>

Name 名称	Initial 初始	Comment 注释
SMC_MAC_INITIALIZATION_FAILED	65	Initialization of SMC_MultiAcyclicCommunicator not successful SMC_MultiAcyclicCommunicator 初始化不成功
SMC_MAC_INVALID_TASK_HANDLE	66	The axis has got an invalid handle 该轴获取了一个无效的句柄
SMC_MAC_TOO_MANY_TASKS	67	Too many tasks with SDO-producing axes SDO-producing axes 的任务太多
SMC_MAC_ATOMIC_ADD_FAILED	68	Atomic add failed 原子加操作失败
SMC_SDO_INVALID_DATA_LENGTH	69	SDO-read lead to invalid datalength (> 4) SDO-read 导致无效的数据长度 (> 4)
SMC_SCM_NOT_SUPPORTED	70	Mode not supported 不支持的模式
SMC_SCM_AXIS_IN_WRONG_STATE	71	In current mode, controller mode cannot be changed. 在当前模式下，控制器模式不能更改。
SMC_SCM_INTERRUPTED	72	SMC_SetControllerMode has been interrupted by MC_Stop or errorstop. SMC_SetControllerMode 已被 MC_Stop 或 errorstop 中断。
SMC_ST_WRONG_CONTROLLER_MODE	75	Axis not in correct controller mode. Deprecated, no longer returned by SMC_SetTorque. 轴未处于正确的控制器模式。已弃用，不再由 SMC_SetTorque 返回。
SMC_RAG_ERROR_DURING_STARTUP	80	Error at startup of the axis group 启动轴组时出错
SMC_RAG_ERROR_AXIS_NOT_INITIALIZED	81	The axis is not yet in the required state. 轴尚未处于所需状态。

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SMC_PP_WRONG_AXIS_TYPE	85	The function block does not support virtual or logical axes. 功能块不支持虚拟或逻辑轴。
SMC_PP_NUMBER_OF_ABSOLUTE_BITS_INVALID	86	The number of absolute bits is invalid, must be in the range 8 .. 32. 绝对位数量无效，必须在 8 .. 32 的范围内。
SMC_NEGATIVE_MODULO_PERIOD	87	The modulo period is negative, this is not supported. 模数周期为负，这不受支持。
SMC_CGR_ZERO_VALUES	90	The value zero is invalid for iRatioTechUnitsNum and dwRatioTechUnitsDenom. iRatioTechUnitsNum 和 dwRatioTechUnitsDenom 的值零无效。
SMC_CGR_DRIVE_POWERED	91	Gearing parameters must not be changed as long as the drive is under control. 只要驱动器处于控制之下，齿轮参数就不得更改。
SMC_CGR_INVALID_POSPERIOD	92	Invalid modulo period (≤ 0 or greater than half the bus bandwidth) 无效的模数周期 (≤ 0 或大于总线带宽的一半)
SMC_CGR_PERIOD_NOT_INTEGRAL	93	The modulo period in increments is not an integer, but the modulo-handling is done by the drive. 增量中的模数周期不是整数，但模数处理由驱动器完成。
SMC_FRACTION_TECH_UNITS_INVALID	94	The fraction describing the conversion between increments and technical units is not initialized properly. (Zero numerator or denominator.) 描述增量与技术单位之间转换的分数未正确初始化。（分子或分母为零。）
SMC_SCALING_PARAMETERS_NOT_POSITIVE	95	The scaling parameters (increments per turn, gear settings, units in application) must be all positive. 缩放参数（每转增量、齿轮设置、应用中的单位）必须全部为正。

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SMC_SCALING_SETTINGS_TOO_LARGE	96	<p>The scaling parameters (increments per turn, gear settings, units in application) are too large to fit into a fraction with 32 bit numerator and denominator.</p> <p>缩放参数（每转增量、齿轮设置、应用中的单位）太大，无法放入一个分子和分母均为 32 位的分数中。</p>
SMC_MODULE_PERIOD_TOO_MANY_DIGITS	97	<p>The modulo period has too many digits. The modulo period times the denominator of the fraction from user units to increments must be an integer.</p> <p>模数周期位数过多。模数周期乘以用户单位到增量的分数的分母必须为整数。</p>
SMC_P_FTASK_CYCLE_EMPTY	110	<p>Axis contain no information on cycle time (fTaskCycle = 0).</p> <p>轴不包含有关周期时间的信息（fTaskCycle = 0）。</p>
SMC_R_NO_ERROR_TO_RESET	120	<p>There is no error to reset.</p> <p>没有错误需要重置。</p>
SMC_R_DRIVE_DOESNT_ANSWER	121	<p>An error occurred trying to acknowledge the drive error.</p> <p>在确认驱动器错误时发生了错误。</p>
SMC_R_ERROR_NOT_RESETTABLE	122	<p>The drive error could not be reset.</p> <p>驱动器错误无法重置。</p>
SMC_R_DRIVE_DOESNT_ANSWER_IN_TIME	123	<p>This error is no longer used and kept only for compatibility reasons. See error SMC_R_ERROR_NOT_RESETTABLE.</p> <p>此错误不再使用，仅保留以保持兼容性。参见错误 SMC_R_ERROR_NOT_RESETTABLE。</p>
SMC_R_CANT_NOT_RESET_COMMUNICATION_ERROR	124	<p>A communication error cannot be acknowledged using MC_Reset. See SMC3_ReinitDrive.</p> <p>无法使用 MC_Reset 确认通信错误。参见 SMC3_ReinitDrive。</p>
SMC_RP_PARAMETER_UNKNOWN	130	<p>Parameter number unknown 参数编号未知</p>
SMC_RP_REQUESTING_ERROR	131	<p>Error during transmission to the drives. See error number in function block instance ReadDriveParameter.</p> <p>向驱动器传输过程中发生错误。参见功能块实例 ReadDriveParameter 中的错误编号。</p>

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SMC_RP_DRIVE_PARAMETER_NOT_MAPPED	132	No assignment for drive parameters available 没有可用的驱动参数分配
SMC_RP_PARAMETER_CONVERSION_ERROR	133	Conversion of the value to / from the drive parameters failed. 值与驱动参数之间的转换失败。 Unknown SoftMotion parameters 未知 SoftMotion 参数
SMC_WP_PARAMETER_INVALID	140	Parameter number unknown or writing not allowed 参数编号未知或不允许写入
SMC_WP_SENDING_ERROR	141	See error number in function block instance WriteDriveParameter 查看函数块实例 WriteDriveParameter 中的错误编号
SMC_WP_DRIVE_PARAMETER_NOT_MAPPED	142	No assignment for drive parameters available 没有可用的驱动参数分配
SMC_WP_PARAMETER_CONVERSION_ERROR	143	Conversion of the value to / from the drive parameters failed 将值转换为/从驱动参数转换失败 Unknown SoftMotion parameters 未知 SoftMotion 参数
SMC_H_AXIS_WASNT_STANDSTILL	170	Axis was not in standstill state. 轴未处于停止状态。
SMC_H_AXIS_DIDNT_START_HOMING	171	Drive did not start homing. 驱动器未开始归位。
SMC_H_AXIS_DIDNT_ANSWER	172	Drive did not reply, when homing was done. 驱动器在归位完成时未回复。
SMC_H_ERROR_WHEN_STOPPING	173	Error at stop after homing. Deceleration may not be set. 归位后停止时出错。减速率可能未设置。

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SMC_H_AXIS_IN_ERRORSTOP	174	Drive is in errorstop status. Homing cannot be executed. 驱动器处于错误停止状态。归位无法执行。
SMC_H_SET_OP_MODE_HOMING_FAILED	175	Drive could not be switched to homing mode. 驱动器无法切换到归位模式。
SMC_H_CHECK_SET_OP_MODE_HOMING_FAILED	176	Drive did not report that it is in homing mode. 驱动器未报告处于归位模式。
SMC_H_PRE_HOMING_CHECKS_FAILED	177	Pre homing checks failed. 归位前的检查失败。
SMC_MS_UNKNOWN_STOPPING_ERROR	180	Unknown error at stop 停止时出现未知错误。
SMC_MS_INVALID_ACCELERATION_VALUES	181	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_MS_DIRECTION_NOT_APPLICABLE	182	Direction = shortest not applicable 方向 = 最短不适用
SMC_MS_AXIS_IN_ERRORSTOP	183	Drive is in errorstop status. Stop cannot be executed 驱动器处于错误停止状态。停止无法执行
SMC_BLOCKING_MC_STOP_WASNT_CALLED	184	Instance of MC_Stop blocking the axis by Execute = TRUE has not been called yet. MC_Stop (Execute = FALSE) has to be called. 实例 MC_Stop 通过 Execute = TRUE 阻挡轴尚未被调用。必须调用 MC_Stop (Execute = FALSE) 。
SMC_MS_AXIS_ALREADY_STOPPING	185	Cannot interrupt an ongoing MC_Stop 无法中断正在进行的 MC_Stop
SMC_UNKNOWN_TASK_INTERVAL	200	The task interval of the bus task could not be determined. 无法确定总线任务的执行间隔。

Name 名称	Initial 初始	Comment 注释
SMC_MA_INVALID_VELOCITY_VALUES	201	Invalid velocity or acceleration values velocity 或 acceleration 值无效
SMC_MA_INVALID_DIRECTION	202	Direction error 方向错误
SMC_MR_INVALID_VELOCITY_VALUES	226	Invalid velocity or acceleration values velocity 或 acceleration 值无效
SMC_MR_INVALID_DIRECTION	227	Direction error 方向错误
SMC_OVR_INVALID_OVERRIDE_FACTORS	231	Invalid velocity, acceleration or jerk override factor 无效的速度、加速度或过冲系数
SMC_INVALID_AXIS_FORECAST	235	Invalid (either negative or too large) axis forecast 无效（负值或过大）的轴预测
SMC_AXIS_FORECAST_NOT_SUPPORTED	236	Axis does not support setting a forecast 轴不支持设置预测
SMC_MAD_INVALID_VELOCITY_VALUES	251	Invalid velocity or acceleration values velocity 或 acceleration 值无效
SMC_MAD_INVALID_DIRECTION	252	Direction error 方向错误
SMC_MSI_INVALID_VELOCITY_VALUES	276	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_MSI_INVALID_DIRECTION	277	Direction error 方向错误

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SMC_MSI_INVALID_EXECUTION_ORDER	278	Except from aborting, don't call a major mvt-FB after SMC_MoveSuperimposed 除了中止之外，不要在 SMC_MoveSuperimposed 后调用主要的 mvt-FB
SMC_LOGICAL_NO_REAL_AXIS	300	No longer used; only for compatibility 不再使用；仅用于兼容性
SMC_MV_INVALID_ACCDEC_VALUES	301	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_MV_DIRECTION_NOT_APPLICABLE	302	Direction = shortest/fastest not applicable Direction = shortest / fastest 不适用
SMC_PP_ARRAY_SIZE	325	Erroneous array size 数组大小错误
SMC_PP_STEP_TIME	326	Step time = t#0s 步进时间 = t#0s
SMC_VP_ARRAY_SIZE	350	Erroneous array size 数组大小错误
SMC_VP_STEP_TIME	351	Step time = t#0s 步进时间 = t#0s
SMC_AP_ARRAY_SIZE	375	Erroneous array size 数组大小错误
SMC_AP_STEP_TIME	376	Step time = t#0s
SMC_TP_TRIGGER_OCCUPIED	400	Trigger already active 触发器已激活
SMC_TP_COUNTDOWN_WINDOW	401	DriveInterface does not support the window function. DriveInterface 不支持窗口函数。
SMC_TP_COMM_ERROR	402	Communication error 通信错误

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SMC_TRIGGER_OUT_OF_RANGE	403	The trigger number is not in the allowed range. 触发号码不在允许的范围内。
SMC_LATCH_IN_CONTROLLER_NOT_SUPPORTED	404	The mode latch in controller got deprecated and is not supported anymore. 控制器中的模式锁存器已过时，不再受支持。
SMC_AT_TRIGGER_NOT_OCCUPIED	410	Trigger already de-allocated 触发器已释放
SMC_MCR_INVALID_VELOCITY_VALUES	426	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_MCR_INVALID_DIRECTION	427	Invalid direction 无效方向
SMC_MCA_INVALID_VELOCITY_VALUES	451	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_MCA_INVALID_DIRECTION	452	Invalid direction 无效方向
SMC_MCA_DIRECTION_NOT_APPLICABLE	453	Direction = fastest not applicable 方向 = 最快不适用
SMC_SDL_INVALID_AXIS_STATE	475	SMC_ChangeDynamicLimits may only be called in state standstill. or power_off. SMC_ChangeDynamicLimits 仅能在停止状态或 power_off 状态下调用。
SMC_SDL_INVALID_VELOCITY_VALUES	476	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_SACF_INVALID_DYNAMIC_FACTOR	480	SMC_SetAdditionalConversionFactors: One of the factors has an invalid value. SMC_SetAdditionalConversionFactors：其中一个因子的值无效。

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SMC_INVALID_VELACCJERK_VALUES	501	Invalid Velocity , Acceleration , Deceleration , or Jerk values 无效的 Velocity 、 Acceleration 、 Deceleration 或 Jerk 值
SMC_INVALID_DIRECTION	502	Invalid Direction
SMC_CR_NO_TAPPETS_IN_CAM	600	Cam does not contain any tappets. Cam 不包含任何挺杆。
SMC_CR_TOO_MANY_TAPPETS	601	Tappet group ID exceeds MAX_NUM_TAPPETS 挺杆组 ID 超过 MAX_NUM_TAPPETS
SMC_CR_MORE_THAN_32_ACCESSES	602	More than 32 accesses on one CAM_REF 在一个 CAM_REF 上有超过 32 次访问
SMC_CI_NO_CAM_SELECTED	625	No cam selected 未选择相机
SMC_CI_MASTER_OUT_OF_SCALE	626	Master axis out of valid range 主轴超出有效范围
SMC_CI_RAMPIN_NEEDS_VELOCITY_VALUES	627	Velocity and acceleration values must be specified for ramp_in function ramp_in 函数必须指定 Velocity 和 acceleration 值
SMC_CI_SCALING_INCORRECT	628	Scaling variables fEditor/TableModelMin/Max are not correct 缩放变量 fEditor / TableMasterMin/Max 不正确
SMC_CI_TOO_MANY_TAPPETS_PER_CYCLE	629	Too many tappets became active during one cycle 在一个周期内，太多的挺杆变得活跃
SMC_CI_MORE_THAN_32_ACCESSES	630	More than 32 accesses on one CAM_REF 在一个 CAM_REF 上有超过 32 次访问

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SMC_CI_MASTER_SYNC_POSITION_OUT_OF_SCALE	631	MasterSyncPosition out of valid range MasterSyncPosition 超出有效范围
SMC_CI_AVOID_REVERSAL_FOR_FINITE_AXIS	632	Input AvoidReversal must not be set for finite slave axes. 对于有限从轴，输入 AvoidReversal 不得设置。
SMC_CI_MASTER_START_DISTANCE_MUST_BE_ZERO_BUFFERED	633	If BufferMode is not Aborting, then MasterStartDistance must not be positive. 如果 BufferMode 不是 Aborting，则 MasterStartDistance 不得为正。
SMC_CI_CAM_CHANGED_DURING_RAMP_IN_DIST	634	The input CamTableId changed while ramping in with start mode ramp_in_dist 在以 ramp_in_dist 启动模式 ramping 输入时，CamTableId 发生了变化
SMC_CB_NOT_IMPLEMENTED	640	Function block for the given cam format is not implemented 给定 cam 格式的功能块尚未实现
SMC_GI_RATIO_DENOM	675	RatioDenominator = 0
SMC_GI_INVALID_ACC	676	Acceleration invalid
SMC_GI_INVALID_DEC	677	Deceleration invalid Deceleration 无效
SMC_GI_MASTER_REGULATOR_CHANGED	678	Master changed regulator state (on -> off or off -> on) while coupling with slave was active. 在从设备耦合激活时，主设备改变了调节器状态（开 -> 关或关 -> 开）。
SMC_GI_INVALID_JERK	679	Jerk invalid Jerk 无效
SMC_PH_INVALID_VELOCITY_DEC	725	Velocity and acceleration/deceleration values invalid Velocity 和 acceleration / deceleration 值无效

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SMC_PH_ROTARY_AXIS_PERIOD0	726	Rotation axis with fPositionPeriod = 0 旋转轴与 fPositionPeriod = 0
SMC_MASTER_REGULATOR_CHANGED	727	Master changed regulator state (on -> off or off -> on) while coupling with slave was active. 在从设备耦合激活时，主设备改变了调节器状态（开 -> 关或关 -> 开）。
SMC_NO_CAM_REF_TYPE	750	Type of given cam is not MC_CAM_REF. 给定凸轮的类型不是 MC_CAM_REF。
SMC_CAM_TABLE_DOES_NOT_COVER_MASTER_SCALE	751	Master area, xStart and xEnd , from CamTable is not covered by curve data. 主区域， xStart 和 xEnd ，来自 CamTable 没有被曲线数据覆盖。
SMC_CAM_TABLE_EMPTY_MASTER_RANGE	752	Cam data table has empty master range. Cam 数据表的主范围是空的。
SMC_CAM_TABLE_INVALID_MASTER_MINMAX	753	Cam data master has invalid max-, min-values. Cam 数据主有无效的最大值、最小值。
SMC_CAM_TABLE_INVALID_SLAVE_MINMAX	754	Cam data slave has invalid max-, min-values. Cam 数据从有无效的最大值、最小值。
SMC_CAM_INVALID_ELEMENT_COUNT	755	The element count of the cam must be > 0. 镜头元素数量必须 > 0。
SMC_CAM_UNKNOWN_SEGMENT_TYPE	756	Unknown cam segment type encountered. 遇到未知的镜头段类型。
SMC_SAFE_CAM_REF_ONLY_ONE_ACCESS_ALLOWED_AT_A_TIME	757	CAM_REF_MULTICORE_SAFE can only be accessed by 1 read or 1 write at a time. CAM_REF_MULTICORE_SAFE 只能同时被 1 次读取或 1 次写入访问。

Name 名称	Initial 初始	Comment 注释
SMC_CAM_REF_INSUFFICIENT_MEMORY	758	<p>The data array of MC_CAM_REF is too small to fit all cam elements.</p> <p>MC_CAM_REF 的数据数组太小，无法容纳所有镜头元素。</p>
SMC_GIP_MASTER_DIRECTION_CHANGE	775	<p>Obsolete: During coupling of slave axis, master axis has changed direction of rotation.</p> <p>过时：在从轴耦合过程中，主轴已改变旋转方向。</p>
SMC_GIP_SLAVE_REVERSAL_CANNOT_BE_AVOIDED	776	<p>Obsolete: Input AvoidReversal is set, but slave reversal cannot be avoided.</p> <p>过时：输入 AvoidReversal 已设置，但无法避免从轴反转。</p>
SMC_GIP_AVOID_REVERSAL_FOR_FINITE_AXIS	777	<p>Input AvoidReversal must not be set for finite slave axes.</p> <p>对于有限从轴，输入 AvoidReversal 不得设置。</p>
SMC_GIP_MASTER_START_DISTANCE_MUST_BE_ZERO_BUFFERED	778	<p>If BufferMode is not Aborting, then MasterStartDistance must not be positive.</p> <p>如果 BufferMode 不是 Aborting，则 MasterStartDistance 不得为正。</p>
SMC_GIP_CANNOT_START_SYNC	779	<p>The synchronisation cannot be started. This can happen when GearInPos is commanded as a buffered or blending movement and the master is in standstill when it becomes active.</p> <p>同步无法启动。这发生在 GearInPos 被命令为缓冲或混合运动，而主轴在它激活时处于静止状态时。</p>
SMC_RAMP_IN_MASTER_DIRECTION_CHANGED	780	<p>During coupling of slave axis, master axis has changed direction of rotation.</p> <p>在从轴耦合过程中，主轴旋转方向已改变。</p>
SMC_RAMP_IN_SLAVE_REVERSAL_CANNOT_BE_AVOIDED	781	<p>Input AvoidReversal is set, but slave reversal cannot be avoided.</p> <p>输入 AvoidReversal 已设置，但无法避免从轴反转。</p>
SMC_DCS_ON_OFF_COMPENSATION_REQUIRES_FORECAST	790	<p>Using a negative On or OffCompensation requires setting a forecast.</p> <p>使用负的 On 或 OffCompensation 需要设置预测。</p>

Name 名称	Initial 初始	Comment 注释
SMC_DCS_ON_OFF_COMPENSATION_EXCEEDS_FORECAST	791	The forecast must not be less than the maximum absolute value of all negative On/OffCompensations. 预报值不能小于所有负 On/OffCompensations 的最大绝对值。
SMC_DCS_SWITCHES_MUST_BE_ORDERED_BY_POSITION	792	Switches on the same track must be ordered by position. 同一条轨道上的开关必须按位置排序。
SMC_DCS_SWITCHES_MUST_NOT_OVERLAP	793	Switches on the same track must not overlap. 同一条轨道上的开关不能重叠。
SMC_DCS_INVALID_TRACK_NUMBER	794	Switch has an invalid track number. 开关具有无效的轨道编号。
SMC_DCS_MAXIMUM_SWITCHES_PER_TRACK_EXCEEDED	795	Maximum number of switches for a track exceeded. 轨道的开关数量已超过最大值。
SMC_DCS_SWITCH_POSITION_OUTSIDE_MODULO_PERIOD	796	At least one of the switches lies outside the modulo period of the axis. 至少有一个开关位于轴的模数周期之外。
SMC_DCS_CAM_SWITCH_POINTER_NOT_SET	797	The Switches.CamSwitchPtr is not set. Switches.CamSwitchPtr 未设置。
SMC_BC_BACKLASH_TOO_BIG	800	Gear backlash fBacklash too large (> position periode/2) 齿轮间隙 fBacklash 过大 (>位置周期/2)
SMC_QPROF_DIVERGES	825	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_QPROF_INVALID_PARAMETER	826	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败

Name 名称	Initial 初始	Comment 注释
SMC_QPROF_NO_RESULT	827	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_QPROF_INVALID_NEW_LBD	828	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_QPROF_BAD_NEGOTIATION	829	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_QPROF_INVALID_INTERVAL	830	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_QPROF_NOT_ENOUGH_PHASES	831	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_TG_INTERNAL_ERROR	832	Internal error: computation of quadratic trajectory failed 内部错误：二次轨迹计算失败
SMC_SRT_NOT_STANDSTILL_OR_POWER_OFF	850	Action only permitted in standstill or power_off . 操作仅在 standstill 或 power_off 中允许。
SMC_SRT_INVALID_RAMP_TYPE	851	Invalid ramp type 无效的斜坡类型
SMC_SMT_NOT_STANDSTILL_OR_POWER_OFF	852	Action only permitted in standstill or power_off . 操作仅在 standstill 或 power_off 中允许。
SMC_SMT_INVALID_MOVEMENTTYPE_OR_POSITIONPERIOD	853	Invalid motion type or position period 无效的运动类型或位置周期
SMC_SMT_AXIS_NOT_VIRTUAL	854	Function block only applicable to virtual axis. 功能块仅适用于虚拟轴。

Name 名称	Initial 初始	Comment 注释
SMC_NO_LICENSE	1000	Target is not licensed for CNC. 目标未获得 CNC 授权。
SMC_INT_VEL_ZERO	1001	Path cannot be processed because set velocity = 0. 路径无法处理，因为设置了 velocity = 0。
SMC_INT_NO_STOP_AT_END	1002	Last object of path has end velocity <> 0. 路径的最后一个对象具有非零的末端速度。
SMC_INT_DATA_UNDERRUN	1003	<p>Warning: GEOINFO-List processed in DataIn but end of list not reached.</p> <p>警告：在 DataIn 中处理了 GEOINFO-List，但未达到列表末尾。</p> <p>Reason: 原因：</p> <ul style="list-style-type: none"> EndOfList of the queue in DataIn not be set 在 DataIn 中的队列 EndOfList 未设置 SMC_Interpolator faster than path generating function blocks SMC_Interpolator 比路径生成函数块更快
SMC_INT_VEL_NONZERO_AT_STOP	1004	Velocity at Stop > 0 停止速度 > 0
SMC_INT_TOO_MANY_RECURSIONS	1005	Too much SMC_Interpolator recursions. SoftMotion error SMC_Interpolator 递归过多。SoftMotion 错误
SMC_INT_NO_CHECKVELOCITIES	1006	SMC_CheckVelocities is not the last processed function block, that accesses to the OutQueue-data by poqDataIn . SMC_CheckVelocities 不是最后处理的函数块，通过 poqDataIn 访问 OutQueue 数据。
SMC_INT_PATH_EXCEEDED	1007	Internal or numeric error 内部或数值错误
SMC_INT_VEL_ACC_DEC_ZERO	1008	Velocity and acceleration / deceleration is null or too low Velocity 和 acceleration / deceleration 为空或过低

Name 名称	Initial 初始	Comment 注释
SMC_INT_DW IPOTIME_ZERO	1009	FB called with <code>dwIpoTime = 0</code> 使用 <code>dwIpoTime = 0</code> 调用 FB
SMC_INT_JERK_NONPOSITIVE	1010	<code>Jerk</code> invalid because <code>jerk</code> must be positive <code>Jerk</code> 无效，因为 <code>jerk</code> 必须为正数
SMC_INT_QPROF_DIVERGES	1011	Internal error. Computation of the quadratic velocity profile does not converge. 内部错误。二次速度分布的计算不收敛。
SMC_INT_INVALID_VELOCITY_MODE	1012	Invalid velocity mode 无效的速度模式
SMC_INT_TOO_MANY_AXES_INTERPOLATED	1013	More than the allowed number of axes has been interpolated. You are using a restricted version. 插值轴数超过允许数量。您正在使用受限版本。
SMC_INT_DEGENERATE_SEGMENT	1014	The segment is numerically degenerate: It is very short and at the end of the queue. It should be ignored. 该段在数值上退化：它非常短，位于队列末尾。应该被忽略。
SMC_HIGH_CURVATURE_SPLINE	1015	Computation of interpolation point failed because the curvature of the spline is too high. Try changing the path to avoid sharp corners. 插值点计算失败，因为样条的曲率过高。尝试更改路径以避免尖锐的角落。
SMC_INT_PROBE_ACKNOWLEDGED_WHILE_MOVING	1016	A probe (G31) must not be acknowledged while the interpolator is moving. Stop the interpolator first, using the inputs <code>bSlow_Stop</code> , <code>bQuick_Stop</code> , or <code>bEmergency_Stop</code> . 一个探头（G31）在插补器移动时不得确认。首先使用 <code>bSlow_Stop</code> 、 <code>bQuick_Stop</code> 或 <code>bEmergency_Stop</code> 停止插补器。
SMC_INT_PROBE_NOT_ACKNOWLEDGED	1017	A probe (G31) has not been acknowledged. 探头（G31）尚未被确认。
SMC_INT_PROBE_INTERNAL_ERROR	1018	An internal error occurred while acknowledging the probe (G31). 在确认探头（G31）时发生了内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_INT2DIR_BUFFER_TOO_SMALL	1050	Warning: <code>poqDataIn</code> of <code>OutQueue</code> is created too small. Adherence of stops not guaranteed. 警告： <code>poqDataIn</code> 的 <code>OutQueue</code> 创建得太小。停止的保持性无法保证。
SMC_INT2DIR_PATH_FITS_NOT_IN_QUEUE	1051	Path does not go completely in queue. 路径未完全进入队列。
SMC_XINT_INVALID_DIRECTION	1070	Direction input has an invalid value. 方向输入值无效。
SMC_XINT_NO_INTERSECTION	1071	Could not determine position on CNC path for the given x-position. 无法确定给定 x 位置上的 CNC 路径位置。
SMC_WAR_INT_OUTQUEUE_TOO_SMALL	1080	Warning: <code>poqDataIn</code> of <code>OutQueue</code> is created too small. Adherence of stops not guaranteed 警告： <code>poqDataIn</code> 的 <code>OutQueue</code> 创建得太小。停止的吸附可能无法保证。
SMC_WAR_END_VELOCITIES_INCORRECT	1081	Warning: Final velocities inconsistent 警告：最终速度不一致
SMC_CV_ACC_DEC_VELENONPOSITIVE	1100	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_CA_INVALID_ACCELERATION_VALUES	1120	Invalid velocity, acceleration, deceleration, or jerk values 无效的速度、加速度、减速度或加加速度值
SMC_TOK_INCOMPLETE_TOKEN_AT_END_OF_INPUT	1130	The input has been exhausted, but there is still an unfinished token 输入已用尽，但仍有未完成的标记
SMC_TOK_NOT_A_VALID_TOKEN	1131	The input does not match any token type 输入不匹配任何标记类型

Name 名称	Initial 初始	Comment 注释
SMC_TOK_ambiguous_input	1132	The input is ambiguous, it could be more than one token type 输入是模糊的，它可能是多种标记类型之一
SMC_TOK_STRING_TOO_LONG_FOR_TOKEN	1133	The string is too long to be stored in a token. (Too long string literal, variable name or identifier?) 字符串太长，无法存储在令牌中。（太长的字符串字面量、变量名或标识符？）
SMC_TOK_INVALID_NUMLIT	1134	Invalid number literal. 无效的数字字面量。
SMC_PRS_FUNC_DECL_TOO_FEW_ARGUMENTS	1150	Too few arguments provided for function or subprogram inside G-Code 为 G-Code 中的函数或子程序提供的参数太少
SMC_PRS_FUNC_DECL_TOO_MANY_ARGUMENTS	1151	Too many arguments provided for function or subprogram inside G-Code 为 G-Code 中的函数或子程序提供的参数太多
SMC_PRS_FUNC_DECL_WRONG_ARGUMENT_TYPE	1152	Argument types do not match the function or subprogram declaration 参数类型与函数或子程序声明不匹配
SMC_PRS_LOCAL_VARIABLE_NOT_FOUND	1153	Could not find local variable on stack 在栈上找不到局部变量
SMC_PRS_INVALID_STRING	1154	Could not read string from token 无法从标记中读取字符串
SMC_PRS_TOO_MANY_CLOSING_BRACKETS	1155	Got more closing than opening brackets 关闭括号多于开启括号
SMC_PRS_TOO_MANY_OPENING_BRACKETS	1156	Got more opening than closing brackets 括号开启多于关闭

Name 名称	Initial 初始	Comment 注释
SMC_PRS_NO_SUCH_INFIX_OPERATOR	1157	Did not find infix-operator 未找到中缀运算符
SMC_PRS_NO_SUCH_PREFIX_OPERATOR	1158	Did not find prefix-operator 未找到前缀运算符
SMC_PRS_OPERATOR_INVALID_PRECEDENCE	1159	Got two operators with equal precedence but non-equal associativity 存在两个优先级相同但结合性不同的运算符
SMC_PRS_NOT_A_TERM	1160	Expected a valid term 期望一个有效的术语
SMC_PRS_EXPRESSION_INVALID_SEQUENCE	1161	Found invalid sequence of tokens inside expression 在表达式中发现无效的标记序列
SMC_PRS_TOO_MANY_TERMS	1162	Got more terms than expected 得到比预期更多的术语
SMC_PRS_STACK_OVERFLOW	1163	Could not parse an expression because the stack is too small 由于栈太小而无法解析表达式
SMC_PRS_VARIABLE_NAME_ALREADY_USED	1164	The name of a subprogram parameter or variable is already used for a different subprogram parameter or variable. 子程序参数或变量的名称已被用于不同的子程序参数或变量。
SMC_PRS_INCOMPLETE_SENTENCE_INPUT_TOKEN_QUEUE	1165	The input token queue of the g-code parser does not hold a complete g-code sentence. G 代码解析器的输入标记队列不包含完整的 G 代码语句。
SMC_PRS_TOO_MANY_SUBPROGRAMS	1167	The subprogram declaration could not be stored because the symbol table capacity has been exceeded. The capacity of the symbol table can be changed with the library parameter SMC_CNC_LibParams.MAX_SUBPROGRAMS. 由于符号表容量已超出，子程序声明无法存储。符号表的容量可以通过库参数 SMC_CNC_LibParams.MAX_SUBPROGRAMS 进行更改。

Name 名称	Initial 初始	Comment 注释
SMC_PRS_TOO_MANY_SUBPROGRAM_PARAMETERS	1168	<p>The maximum number of subprogram parameters has been exceeded. This maximum number can be changed with the library parameter <code>SMC_CNC_LibParams.MAX_SUBPROGRAM_PARAMS</code>.</p> <p>子程序参数的最大数量已超出。此最大数量可以通过库参数 <code>SMC_CNC_LibParams.MAX_SUBPROGRAM_PARAMS</code> 进行更改。</p>
SMC_PRS_SUBPROGRAM_LOOKUP_FAILED	1169	<p>The lookup of the subprogram declaration failed. Maybe the subprogram name is incorrect, or the search path for subprograms is incomplete. Is the file name all lower case?</p> <p>查找子程序声明失败。可能是子程序名称不正确，或者子程序的搜索路径不完整。文件名是否全部小写？</p>
SMC_PRS_VARIABLE_NOT_FOUND	1170	<p>Did not find variable in symbol table</p> <p>在符号表中未找到变量</p>
SMC_PRS_TOKEN_TYPE_UNKNOWN	1171	Token type unknown 未知标记类型
SMC_PRS_GOT_NO_TERM	1172	No term after G-address G-address 后没有术语
SMC_PRS_INVALID_VARIABLE_TYPE	1173	<p>Unknown variable type (not LREAL, BOOL, or STRING).</p> <p>未知变量类型（不是 LREAL、BOOL 或 STRING）。</p>
SMC_PRS_UNEXPECTED_TOKEN	1174	<p>A token of a different type (e.g. an operator or identifier) was expected here.</p> <p>此处预期的是不同类型的标记（例如运算符或标识符）。</p>
SMC_PRS_IDENTIFIER3_EXPECTED	1175	<p>An identifier with length three or longer was expected here.</p> <p>此处预期有一个长度至少为三的标识符。</p>
SMC_PRS_IDENTIFIER_TOO_LONG	1176	<p>The identifier is too long (more than 80 characters).</p> <p>标识符过长（超过 80 个字符）。</p>
SMC_PRS_GADDRESS_EXPECTED	1177	<p>A G-address (such as 'G', 'F', 'X') was expected here.</p> <p>此处应期望一个 G 地址（例如'G'、'F'、'X'）。</p>

Name 名称	Initial 初始	Comment 注释
SMC_PRS_N WORD_EXPECTED	1178	An N-word (such as 'N10') was expected here. 此处应期望一个 N 字（例如'N10'）。
SMC_PRS_N WORD_INVALID_SENTENCE_NUMBER	1179	The sentence number is not in the range [0, ..., 16#FFFFFFFF]. 句子编号不在 [0, ..., 16#FFFFFFFF] 范围内。
SMC_PRS_N WORD_SENTENCE_NUMBER_NO_NUMBER_LITERAL	1180	The sentence number must be a number literal. (For example, expressions are not allowed.) 句子编号必须是一个数字字面量。（例如，不允许使用表达式。）
SMC_PRS_USE_OF_RESERVED_KEYWORD	1181	The identifier is a keyword reserved for future use that cannot be used here. 标识符是保留用于未来的关键字，此处不能使用。
SMC_PRS_SUBPROGRAMS_SIGNATURE_MISMATCH	1182	The subprogram declaration has already been read with a different signature or an error. 子程序声明已经以不同的签名或错误被读取。
SMC_PRS_INITIAL_VALUE_HAS_WRONG_TYPE	1183	The initial value has the wrong type for this local variable 这个局部变量的初始值类型不正确
SMC_PRS_TOO_MANY_LOCAL_VARIABLES	1184	The maximum number of local variables has been exceeded. This maximum number can be changed with the library parameter SMC_CNC_LibParams.MAX_SUBPROGRAM_PARAMS. 局部变量的最大数量已超出。此最大数量可以通过库参数 SMC_CNC_LibParams.MAX_SUBPROGRAM_PARAMS 进行更改。
SMC_PRS_SUBPROGRAM_MUST_BE_FIRST_SENTENCE	1185	A subprogram declaration must be the first sentence in a g-code file. 子程序声明必须是 g-code 文件中的第一行。
SMC_PRS_ONLY_ONE_SUBPROGRAM_PER_FILE_ALLOWED	1186	Only one subprogram is allowed in a g-code file. g-code 文件中只允许有一个子程序。

Name 名称	Initial 初始	Comment 注释
SMC_PRS_LET_AFTER_REGULAR_SENTENCE	1187	A LET declaration is not allowed after a regular g-code sentence. LET 声明不允许在常规 g 代码句子之后。
SMC_PRS_UNMATCHED_END_SUBPROGRAM	1188	The END_SUBPROGRAM sentence is not matched by a subprogram declaration. END_SUBPROGRAM 句子与子程序声明不匹配。
SMC_PRS_UNEXPECTED_TOKENS_AFTER_SUBPROGRAM	1189	After END_SUBPROGRAM, no more tokens are allowed. END_SUBPROGRAM 之后不允许再有标记。
SMC_PRS_MISSING_END_SUBPROGRAM	1190	A subprogram is not terminated by END_SUBPROGRAM. 子程序不是由 END_SUBPROGRAM 终止的。
SMC_PRS_USE_OF_KEYWORD	1191	The identifier is a keyword that cannot be used here. 标识符是一个在此处不能使用的关键字。
SMC_PRS_DYNCALL_EXPECTED_SUBNAME_EXP	1192	The first argument to a DYNCALL must be an expression for the subprogram name. DYNCALL 的第一个参数必须是子程序名称的表达式。
SMC_PRS_DYNCALL_EXPECTED_SUBNAME_TYPE_STRING	1193	The first argument to a DYNCALL (subprogram name) must have type STRING. DYNCALL 的第一个参数（子程序名称）必须为 STRING 类型。
SMC_DEC_ACC_TOO_LITTLE	1200	Acceleration value impermissible Acceleration 值不允许
SMC_DEC_RET_TOO_LITTLE	1201	Deceleration value impermissible Deceleration 值不允许
SMC_DEC_OUTQUEUE_RAN_EMPTY	1202	Data underrun. Queue has been read and is empty. 数据下溢。队列已被读取且为空。

Name 名称	Initial 初始	Comment 注释
SMC_DEC_JUMP_TO_UNKNOWN_LINE	1203	Jump to line cannot be executed because line number is unknown. 无法执行跳转到行，因为行号未知。
SMC_DEC_INVALID_SYNTAX	1204	Syntax invalid 语法无效
SMC_DEC_3D_MODE_OBJECT_NOT_SUPPORTED	1205	Objects are not supported in 3D mode. 对象在 3D 模式下不受支持。
SMC_DEC_NEGATIVE_PERIOD	1206	Negative value as a period of additional axes invalid 作为附加轴的负值无效。
SMC_DEC_DIMENSIONS_EXCLUSIVE_AU	1207	Not both axes A and U are interpolated. PA and PU are mutually exclusive. 轴 A 和 U 不能同时插值。PA 和 PU 是互斥的。
SMC_DEC_DIMENSIONS_EXCLUSIVE_BV	1208	Not both axes B and V are interpolated. PB and PV are mutually exclusive. 轴 B 和 V 不能同时插值。PB 和 PV 是互斥的。
SMC_DEC_DIMENSIONS_EXCLUSIVE_CW	1209	Not both axes C and W are interpolated. PC and PW are mutually exclusive. C 和 W 轴不能同时进行插补。PC 和 PW 是互斥的。
SMC_DEC_DCS_NOT_ALL_OF_ABC_GIVEN	1210	For G54/G55/G56, either all of A,B,C or none must be given if orientation mode is not equal to SMC_ORI_CONVENTION.ADDAXES. 在方向模式不等于 SMC_ORI_CONVENTION.ADDAXES 的情况下，对于 G54/G55/G56，必须全部给出 A、B、C 或全部不给出。
SMC_DEC_DCS_2D_NOT_IN_XY_PLANE	1211	The z-axis of the decoder CS must be equal to the z-axis of the machine CS. 解码器 CS 的 z 轴必须等于机器 CS 的 z 轴。
SMC_DEC_CIRCLES_NON_UNIFORM_SCALING	1212	Scaling would distort commanded circle or ellipse. 缩放会扭曲指令圆或椭圆。

Name 名称	Initial 初始	Comment 注释
SMC_DEC_ROTATION_AFFECTS_SCALING	1213	New relative rotation of the DCS (G55) would affect the scaling DCS（G55）的新相对旋转会影响缩放
SMC_DEC_DCS_NOT_ALL_OF_IJK_GIVEN	1214	For G54/G55/G56, either all of I,J,K or none must be given. 对于 G54/G55/G56，必须全部给出 I，J，K 或全部不给出。
SMC_IPR_LOCAL_VAR_UNKNOWN_TYPE	1250	Local variable cannot be read due to invalid type 由于类型无效，无法读取局部变量
SMC_IPR_LOCAL_VARIABLE_WRONG_TYPE	1251	The variable that's supposed to be written on does not have the correct type. 要写入的变量的类型不正确。
SMC_IPR_EVAL_STACK_OVERFLOW	1252	Could not evaluate an expression because the evaluation stack is too small. You can change the size of the eval stack with the library parameter SMC_CNC_LibParams.EVAL_STACK_SIZE. 无法评估表达式，因为评估栈太小。您可以通过库参数 SMC_CNC_LibParams.EVAL_STACK_SIZE 更改评估栈的大小。
SMC_IPR_NOT_A_NUMBER	1253	Numeric term became NaN 数值项变为 NaN
SMC_IPR_DIVISION_BY_ZERO	1254	Division by zero 除以零
SMC_IPR_INVALID_SCALING_FACTORS	1255	Invalid scaling factors 无效的缩放因子
SMC_IPR_INTERPRETER_STACK_IMBALANCE	1256	On subprogram return, the interpreter stack ran empty. Internal error. 在子程序返回时，解释器栈已为空。内部错误。
SMC_IPR_INTERPRETER_STACK_OVERFLOW	1257	The interpreter stack is too small. Too many local variables in the g-code or too many subprograms active. 解释器栈太小。g-code 中的局部变量过多或激活的子程序过多。

Name 名称	Initial 初始	Comment 注释
SMC_IPR_INVALID_INTERPRETER_STACK_BUFFER	1258	The given buffer for the interpreter stack is either 0 or smaller than 1024 bytes. 为解释器栈提供的缓冲区要么为 0，要么小于 1024 字节。
SMC_IPR_BUFFER_TOO_SMALL	1259	The buffer for the outqueue is too small. 出队队列的缓冲区太小。
SMC_NO_PROBE_ALLOWED	1260	For this sentence type the PROBE word is not allowed 对于这种句子类型，不允许输入 PROBE 单词
SMC_AT_MOST_ONE_PROBE_ALLOWED	1261	At most one probe word is allowed per sentence 每句最多允许一个探测单词
SMC_PROBE_NON_POSITIVE	1262	The probe number must be positive 探测数字必须是正数
SMC_PROBE_TOO_LARGE	1263	The probe number exceeds an unsigned 32 bit integer 探测数字超过无符号 32 位整数
SMC_NO_HFUNCTION_ON_PROBE_ALLOWED	1264	H-functions not allowed for probe movements (G31). H 函数不允许用于探测移动（G31）。
SMC_ARC_2D_MODE_K_AND_T_DETERMINE_APEX	1265	In 2.5D mode, both K and T define the apex. Only one may be used. 在 2.5D 模式下，K 和 T 都定义顶点。只能使用其中一个。
SMC_ARC_RADIUS_AND_APEX_OR_CENTER_GIVEN	1266	If the radius is used with R, apex (T/K) and center (I/J/K) must not be used. 如果使用 R 指定半径，则不能同时使用顶点（T/K）和中心（I/J/K）。
SMC_ARC_CENTER_NOT_GIVEN	1267	The center (I/J/K) must be given if no radius is given. 如果没有指定半径，必须给出中心（I/J/K）。
SMC_ARC_DISTANCE_LARGER_THAN_DIAMETER	1268	The distance of start and end-position is larger than two times the radius. See SMC_NCInterpreter.dCircleTolerance. 起始位置和结束位置之间的距离大于半径的两倍。参见 SMC_NCInterpreter.dCircleTolerance。

Name 名称	Initial 初始	Comment 注释
SMC_ARC_DISTANCE_TOO_SMALL	1269	The distance between start- and endposition is almost zero. 起始位置和结束位置之间的距离几乎为零。
SMC_ARC_APEX_TOO_SMALL	1270	The given apex is too small (almost zero). 给定的顶点太小（几乎为零）。
SMC_ARC_APEX_TOO_LARGE	1271	The given apex is larger than 1080. 给定的顶点大于 1080。
SMC_ARC_CENTER_NOT_ORIGINAL_PERPENDICULAR_BISECTOR	1272	The center point is too far from the perpendicular bisector of the start and end point. See SMC_NCIntepreter.dCircleTolerance. 中心点距离起点和终点垂直平分线太远。参见 SMC_NCIntepreter.dCircleTolerance。
SMC_CNC_INVALID_TWO_LETTER_TOKEN	1273	Invalid two letter token. 无效的两字母标记。
SMC_CNC_ONLY_ONE_G_OR_M_WORD_ALLOWED	1274	Only one G or M word is allowed per G-Code sentence. 每个 G 代码句子只允许有一个 G 或 M 字。
SMC_DEC_UNKNOWN_GWORD	1275	This G-word is not supported. 这个 G 字不支持的。
SMC_CNC_POSITION_VALUES_NOT_SUPPORTED	1276	Position values (X/Y/Z/A/B/C/P/Q/U/V/W) are not supported for this G-code sentence. 位置值（X/Y/Z/A/B/C/P/Q/U/V/W）不适用于此 G 代码指令。
SMC_CNC_SPLINE_ABORTED_BY_G75	1277	The preceeding spline has been aborted by G75. 前一个样条曲线已被 G75 中止。
SMC_DNCCS_NO_DATA	1280	No data available at all 完全没有数据可用

Name 名称	Initial 初始	Comment 注释
SMC_DNCCS_TOO_MANY_CALLSTACKS	1281	Too many different callstacks between current state of interpreter and iObjNo 当前解释器状态和 iObjNo 之间存在过多不同的调用栈。
SMC_DNCCS_INVALID_PROGRAM_INDEX	1282	Invalid program index 无效的程序索引
SMC_DNCCS_TOO_MANY_PROGRAMS	1283	Too many different programs 程序过多
SMC_DNCCS_WRONG_TASK	1284	FB called in wrong task FB 在错误的任务中调用
SMC_GCV_BUFFER_TOO_SMALL	1300	Buffer too small 缓冲区太小
SMC_GCV_BUFFER_WRONG_TYPE	1301	Buffer elements have wrong type. 缓冲元素类型错误。
SMC_GCV_UNKNOWN_IPO_LINE	1302	Current line of the Interpolator could not be found. 找不到插值器的当前行。
SMC_CNC_INTERNAL_ERROR	1400	Internal error in CNC CNC 内部错误。
SMC_PATH_MAX_HPOINTS_EXCEEDED	1401	The path element cannot hold H Switch points more than MAX_IPOSWITCHES. Adjust the switching points with different 'O' values or reduce the number of H points per path element. 路径元素不能包含超过 MAX_IPOSWITCHES 的 H 开关点。使用不同的“O”值调整开关点，或减少每个路径元素的 H 点数。
SMC_TRC_G75_NOT_ALLOWED	1410	G75 not allowed during tool radius correction G75 在刀具半径补偿期间不允许使用
SMC_TRC_QUEUE_FULL_NON_CARTESIAN	1411	Queue full, but no further cartesian element 队列已满，但没有进一步的笛卡尔元素

Name 名称	Initial 初始	Comment 注释
SMC_TRC_SP LINE3D_5_NO T_SUPPORTE D	1412	Tool radius correction does not support movement type SPLINE3D_5 刀具半径补偿不支持运动类型 SPLINE3D_5
SMC_TRC_EL LIPSES_NOT_ SUPPORTED	1413	Tool radius correction does not support ellipses 刀具半径补偿不支持椭圆
SMC_TRC_PL ANE_CHANG E_NOT_ALLO WED	1414	Plane change not allowed during tool radius correction 在刀具半径校正期间不允许改变平面
SMC_CNC_IN VALID_GEOIN FO	1415	An invalid path element has been created, probably due to invalid input values (too large tool radius or similar) 已创建无效的路径元素，可能是由于输入值无效（刀具半径过 大或类似原因）
SMC_CNC_CA NNOT_APPEN D_TO_OUTQU EUE	1416	A path element could not be appended to the out queue. Internal error of a path preprocessing function block. 无法将路径元素追加到输出队列。路径预处理功能模块内部错 误。
SMC_CNC_AP PEND_ON_FIR ST_RISING_E DGE	1417	The input bAppend must not be TRUE on the first rising edge of Execute. 在 Execute 的第一个上升沿，输入 bAppend 不能为 TRUE。
SMC_PROBE_ G31_NOT_AL LOWED	1418	This function block does not support probe movements / G31. 此功能块不支持探测运动/G31。
SMC_AL_ELLI PSES_NOT_S UPPORTED	1430	Avoid loops does not support ellipses 避免循环不支持省略号
SMC_NAV_M AX_SUBPROG RAM_NESTIN G_EXCEEDED	1450	The maximum nesting level for subprogram calls has been exceeded. This maximum can be changed with the library parameter SMC_CNC_LibParams.MAX_SUBPROGRAM_NESTING_DEPTH. 子程序调用的最大嵌套级别已超出。此最大值可以通过库参数 SMC_CNC_LibParams.MAX_SUBPROGRAM_NESTING_DEPTH 更改。

Name 名称	Initial 初始	Comment 注释
SMC_NAV_RETURN_FROM_MAIN	1451	A return statement from the main g-code program is not allowed. 不允许从主 G 代码程序中返回。
SMC_NAV_SUBPROGRAM_DECLARATION_NOT_FOUND	1452	The declaration of a subprogram has not been found in the subprogram CNC file. 子程序声明未在子程序 CNC 文件中找到。
SMC_NAV_NEXT_SENTENCE_ENOUGH_SPACE_FOR_COMPLETE_SENTENCE	1453	The next g-code sentence could not be added to the output sentence queue because there was not enough space left. 下一个 g 代码句子无法添加到输出句子队列中，因为剩余空间不足。
SMC_NO_CNC_REF_TYPE	1500	Given CNC program is not of type SMC_CNC_REF 给定的 CNC 程序不是 SMC_CNC_REF 类型。
SMC_NO_OUTQUEUE_TYPE	1501	Given OutQueue is not of type SMC_OUTQUEUE 给定的 OutQueue 不是 SMC_OUTQUEUE 类型。
SMC_GEOINFO_BUFFER_MISALIGNED	1502	4-byte aligned buffer part is not used in pbyBuffer 4 字节对齐的缓冲区部分在 pbyBuffer 中未使用
SMC_3D_MODEL_NOT_SUPPORTED	1600	Function block only works with 2D paths. 函数块仅与 2D 路径一起工作。
SMC_SAA_SMOOTHAREA_TOO_LARGE	1700	Range for smoothing too large 平滑范围过大
SMC_SAA_SP_INVALID_INPUT	1701	Invalid input dSmoothingPart]0..1] 无效输入 dSmoothingPart]0..1]
SMC_SA_QUEUE_NOT_IN_BUFFER	1800	SMC_SegmentAnalyzer detects that OutQueue buffer is full but not completed. The function block can only operate when OutQueue fits the buffer completely. SMC_SegmentAnalyzer 检测到 OutQueue 缓冲区已满但未完成。函数块只能在 OutQueue 完全适配缓冲区时操作。

Name 名称	Initial 初始	Comment 注释
SMC_SA_QUEUE_CHANGED_DURING_OP	1801	OutQueue buffer changed while the function block is operating on them. OutQueue 缓冲区在函数块对其进行操作时发生了变化。
SMC_OS_INVALID_PARAMETER	1820	Invalid input value in dSplittingParameter dSplittingParameter 输入值无效
SMC_BSSP_POSITION_NOT_ACTIVE	1830	Position cannot be saved. Interpolator is inactive 位置无法保存。插值器处于非活动状态
SMC_BS_SAVED_POSITION_NOT_REACHED	1831	Saved position has not been found so far. It is probably on a different path. 至今未找到保存的位置。它可能位于不同的路径上。
SMC_BS_NO_POSITION_STORED	1832	Structure passed in ePos contains no saved position. SMC_BlockSearchSavePos is not executed or in a wrong way. 传入 ePos 的结构中不包含保存的位置。 SMC_BlockSearchSavePos 未执行或执行方式错误。
SMC_INVALID_FEATURE_FLAG	1900	Feature flag must be in the range {1, ..., 31}. 特性标志必须在{1, ..., 31}的范围内。
SMC_SMB_HFUNCTION_NOT_SUPPORTED	1901	Function block does not support h-functions. 功能块不支持 h 函数。
SMC_SMB_ONLY_3D_MODE	1902	Function block only works in 3D-Mode. 功能块仅在 3D 模式下工作。
SMC_SMB_ERROR_COMPUTING_SPLINE	1903	Internal error computing the spline. 计算样条曲线时发生内部错误。
SMC_SMM_INVALID_PARAMETER_NUMBER	1910	wAdditionalParameter is too big wAdditionalParameter 太大。
SMC_ORIENTATION_UNKNOWN	1911	The tangent is zero and no previous orientation has been computed since the last rising edge of Enable. 切线为零，并且自 Enable 的最后一个上升沿以来未计算之前的方向。

Name 名称	Initial 初始	Comment 注释
SMC_NOT_IMPLEMENTED	1949	Feature is not implemented. 该功能尚未实现。
SMC_INVALID_PARAMETER	1950	The value of one of the inputs is invalid. 某个输入值的无效。
SMC_BLENDING_NOT_SUPPORTED_BY_PREVIOUS_MOVEMENT	1951	The previous movement does not support blending. 之前的移动不支持混合。
SMC_BUFFERED_NOT_SUPPORTED_BY_PREVIOUS_MOVEMENT	1952	The previous movement does not support buffered movements. 之前的移动不支持缓冲移动。
SMC_INHERIT_OWNER_ACTIVE_MOVEMENT_NOT_CALLED	1953	Cannot inherit owner because the active movement has not been not called yet in this cycle. Internal error. 无法继承所有者，因为在本周期中，激活的移动尚未被调用。内部错误。
SMC_MOVING_WITHOUT_ACTIVE_MOVEMENT	1954	The axis is moving but there is no active movement function block. Missing follow-up movement after movement that does not end in standstill? 轴正在移动，但没有激活的移动功能块。移动未在静止状态下结束，之后缺少后续移动？
SMC_BUFFER_MODE_NOT_SUPPORTED	1955	The configured BufferMode is not supported by the commanded movement. 配置的 BufferMode 不受命令移动支持。
SMC_ERROR_IN_A_PREVIOUS_MOVEMENT	1956	An error occurred in a previous movement. 在之前的移动中发生了错误。
SMC_MORE_THAN_ONE_MOVEMENT_PER_INSTANCE	1957	Only one busy buffered/blending movement per FB instance is allowed. 每个 FB 实例只允许一个忙缓冲/混合移动。

Name 名称	Initial 初始	Comment 注释
SMC_SUPERIMPOSED_FB_WASNT_CALLED	1958	<p>A superimposed FB (MC_MoveSuperimposed or MC_HaltSuperimposed) that controlled the superimposed movement has not been called in this task cycle.</p> <p>在这个任务周期中，控制叠加移动的叠加 FB（MC_MoveSuperimposed 或 MC_HaltSuperimposed）没有被调用。</p>
SMC_RNCF_FILE_DOESNT_EXIST	2000	File does not exist 文件不存在
SMC_RNCF_NO_BUFFER	2001	No buffer allocated 没有分配缓冲区
SMC_RNCF_BUFFER_TOO_SMALL	2002	Buffer too small 缓冲区太小
SMC_RNCF_DATA_UNDERRUN	2003	<p>Data underrun. Buffer has been read, is empty.</p> <p>数据下溢。缓冲区已被读取，为空。</p>
SMC_RNCF_VARIABLE_COULDNT_BE_REPLACED	2004	<p>Placeholder variable could not be replaced.</p> <p>占位符变量无法替换。</p>
SMC_RNCF_NOT_VARLIST	2005	<p>Input pv1 does not point to a SMC_VARLIST object.</p> <p>输入 pv1 指向的不是 SMC_VARLIST 对象。</p>
SMC_RNCF_NO_STRINGBUFFER	2006	<p>Input pStringBuffer is not used or does not point to a variable of type SMC_StringBuffer</p> <p>输入 pStringBuffer 未被使用或未指向类型为 SMC_StringBuffer 的变量。</p>
SMC_RNCF_STRINGBUFFER_OVERRUN	2007	<p>In the CNC program more different strings are used than the string buffer can hold.</p> <p>在 CNC 程序中使用的不同字符串比字符串缓冲区能容纳的要多。</p>
SMC_RNCF_SUBPROGRAM_FILE_NOT_FOUND	2008	<p>The file for a subprogram could not be found.</p> <p>找不到子程序文件。</p>

Name 名称	Initial 初始	Comment 注释
SMC_RNCF_FILE_CANNOT_DETERMINE_SIZE	2009	The file size could not be determined. 文件大小无法确定。
SMC_RNCQ_FILE_DOESNT_EXIST	2050	File could not be opened. 文件无法打开。
SMC_RNCQ_NO_BUFFER	2051	No buffer defined 未定义缓冲区
SMC_RNCQ_BUFFER_TOO_SMALL	2052	Buffer too small 缓冲区太小
SMC_RNCQ_UNEXPECTED_EOF	2053	Unexpected end of file 文件意外结束
SMC_ADL_FILE_CANNOT_BE_OPENED	2100	File could not be opened 无法打开文件
SMC_ADL_BUFFER_OVERRUN	2101	Buffer overrun. WriteToFile must be called more frequently. 缓冲区溢出。必须更频繁地调用 WriteToFile 。
SMC_RCAM_FILE_DOESNT_EXIST	2200	File could not be opened. 文件无法打开。
SMC_RCAM_TOO_MUCH_DATA	2201	Saved cam too big 保存的相机文件过大
SMC_RCAM_WRONG_COMPILE_TYPE	2202	Wrong compilation mode 编译模式错误
SMC_RCAM_WRONG_VERSION	2203	File has wrong version 文件版本不正确
SMC_RCAM_UNEXPECTED_EOF	2204	Unexpected end of file 文件意外结束

Name 名称	Initial 初始	Comment 注释
SMC_RCAM_WRITE_ERROR	2205	Error writing to the cam file 写入 cam 文件时出错
SMC_RCAM_READ_ERROR	2206	Error reading from the cam file 从 cam 文件读取错误
SMC_WDPF_CHANNEL_OCCUPIED	3001	This error is obsolete and is maintained only for compatibility. SMC_WDPF_TIMEOUT_PREPARING_LIST 此错误已过时，仅保留以兼容。 SMC_WDPF_TIMEOUT_PREPARING_LIST
SMC_WDPF_CANNOT_CREATE_FILE	3002	This error is obsolete and is maintained only for compatibility. File could not be created. 此错误已过时，仅保留以兼容。无法创建文件。
SMC_WDPF_ERROR_WHEN_READING_PARAMETERS	3003	This error is obsolete and is maintained only for compatibility. Error at reading the parameters. 此错误已过时，仅保留以兼容。读取参数时出错。
SMC_WDPF_TIMEOUT_PREPARING_LIST	3004	This error is obsolete and is maintained only for compatibility. Timeout during preparing the parameter list. 此错误已过时，仅保留以保持兼容性。在准备参数列表时超时。
SMC_ENC_DENOM_ZERO	5000	Nominator of the conversion factor <code>dwRatioTechUnitsDenom</code> of the Encoder reference is 0 编码器参考的转换因子 <code>dwRatioTechUnitsDenom</code> 的指定者为 0
SMC_ENC_AXIS_USED_BY_OTHER_FB	5001	Other module trying to process motion on the Encoder axis 其他模块尝试处理编码器轴上的运动
SMC_ENC_FILTER_DEPTH_INVALID	5002	Filter depth is invalid 滤波器深度无效
SMC_INTERNAL_ERROR_IN_INIT_MOVEMENT	6000	An internal error occurred during initialization of a new movement. 初始化新运动时发生内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_INVALID_AXIS_TYPE	6001	Invalid axis type, not finite or modulo (internal error) 轴类型无效，不是有限的或模数的（内部错误）
SMC_PCCQ_POINTBUFFER_TOO_SMALL	10000	Buffer pBuffer too small 缓冲区 pBuffer 太小
SMC_PCCQ_INPUTBUFFER_FULLBUTNOT_FINALIZED	10001	The function block must be applied to a path that fits completely in the buffer. 函数块必须应用于完全适合缓冲区的路径。
SMC_PCCQ_PATH_NOT_COMPLETELY_IN_INPUT_BUFFER	10002	The path is not completely contained in the buffer. 路径未完全包含在缓冲区中。
SMC_AXIS_GROUP_WRONG_STATE	11000	The axis group is in the wrong state for the requested operation. 轴组处于请求操作的不正确状态。
SMC_AXIS_GROUP_TOO_MANY_AXES	11001	More than the maximum allowed number of axes has been added to an axis group. 已向轴组添加了超过最大允许数量的轴。
SMC_AXIS_GROUP_INVALID_DYNAMIC_LIMITS	11002	The dynamic limits of a single axis are invalid. (fSWMaxVelocity/Acceleration/Deceleration/Jerk) 单个轴的动态限制无效。 (fSWMaxVelocity/Acceleration/Deceleration/Jerk)
SMC_AXIS_GROUP_INVALID_COORD_SYSTEM	11004	The given coordinate system is invalid for the requested operation 所提供的坐标系对请求的操作无效
SMC_AXIS_GROUP_SINGLE_AXIS_ERROR	11005	An axis of the axis group is in state error 轴组中的一个轴处于错误状态
SMC_MOVE_INVALID_BUFFER_MODE	11006	The given buffer mode is not supported 所提供的缓冲模式不受支持

Name 名称	Initial 初始	Comment 注释
SMC_MOVE_INVALID_DYNAMIC_FACTOR	11007	The dynamic factor is not in the range]0 .. 1] 动态因子不在范围]0 .. 1]内
SMC_MOVE_INVALID_DYNAMICS	11008	The dynamic limits for the movement are invalid. 运动的有效动态限制无效。
SMC_AXIS_GROUP_AXIS_NOT_PART_OF_GROUP	11009	The given axis is not part of the axis group. 所提供的轴不属于轴组。
SMC_AXIS_GROUP_NOT_SUPPORTED	11010	The requested operation is not supported 请求的操作不受支持。
SMC_AXIS_GROUP_KINEMATICS_NOT_SET	11011	No kinematic configuration has been configured. 未配置运动学配置。
SMC_AXIS_GROUP_WRONG_NUMBER_OF_AXES	11012	The number of axes is not equal to the number of axes needed by the kinematic transformation 轴的数量与运动学变换所需的轴数不相等
SMC_AXIS_GROUP_INTERRUPTED_BY_SINGLE_AXIS	11013	A coordinated movement has been interrupted by a single axis movement. 一个协调运动被单个轴运动中断。
SMC_AXIS_GROUP_FOLLOW_SETVALUES	11014	An error in an axis of the axis group occurred while following the computed set values. 在遵循计算设定值时，轴组中的一个轴发生了错误。
SMC_AXIS_GROUP_TOO_MANY_DEPENDENCIES	11015	An axis group cannot depend on more than one master axis group. 一个轴组不能依赖于多个主轴组。
SMC_AXIS_GROUP_MUTUAL_DEPENDENCY	11016	An axis group A may not depend on another axis group that depends on A. 一个轴组 A 可能不依赖于另一个依赖于 A 的轴组。

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_DEPENDENCY_IN_DIFFERENT_TASK	11017	A dependant axis group must be executed in the same task. 一个依赖轴组必须在同一个任务中执行。
SMC_AXIS_GROUP_AXIS_IN_DIFFERENT_TASK	11018	An axis belonging to an axis group must be executed in the same task. 一个属于轴组的轴必须在同一个任务中执行。
SMC_AXIS_GROUP_PCS_STILL_IN_USE	11019	A second activation of the function block occurred while the PCS was still used by buffered motion commands. 在 PCS 仍然被缓冲运动命令使用时，发生了函数块的第二次激活。
SMC_AXIS_GROUP_CMD_ABORTED_DUE_TO_ERROR	11020	An error occurred in a previous motion command. 在之前的运动命令中发生了错误。
SMC_AXIS_GROUP_INVALID_PARAMETER	11021	A parameter of an administrative function block is invalid. 管理功能块的一个参数无效。
SMC_AXIS_GROUP_UNSUPPORTED_RAMP_TYPE	11022	One of the axes of the group uses an unsupported ramp type. Only trapez and quadratic are supported. 该组的其中一个轴使用了不支持的斜坡类型。仅支持梯形和二次曲线。
SMC_MOVE_INVALID_TRANSITION_PARAMETER	11023	invalid transition parameter 无效的过渡参数
SMC_AXIS_GROUP_CP_TRACKING_CANNOT_FOLLOW	11025	CP-Tracking: Cannot keep the path; try to reduce the dynamics on the path and / or the dynamics when entering CP-Tracking. CP-Tracking: 无法保持路径；尝试减少路径上的动态变化和/或在进入 CP-Tracking 时减少动态变化。

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_CONTINUE_WRONG_POSITION	11026	<p>Current position does not allow continuation. When continuing in a dynamic coordinate system (e.g. in a PCS that is following a rotary table), this error might be caused by not having used SMC_GroupUpdateContinueData.</p> <p>当前位置不允许继续。在动态坐标系中继续（例如，在一个跟随回转台的 PCS 中）时，此错误可能是由于未使用 SMC_GroupUpdateContinueData 引起的。</p>
SMC_AXIS_GROUP_CONTINUE_BUFFER_TOO_SMALL	11027	<p>Buffer in continueData is too small; big external movement-queue-buffer in use.</p> <p>continueData 中的缓冲区太小；正在使用较大的外部运动队列缓冲区。</p>
SMC_AXIS_GROUP_CONTINUE_WRONG_CHECKSUM	11028	<p>The checksum stored in the continue data is wrong. The continue data either was not written by MC_GroupInterrupt, or was modified afterwards.</p> <p>继续数据中存储的校验和错误。继续数据要么是由 MC_GroupInterrupt 未写入，要么是之后被修改了。</p>
SMC_AXIS_GROUP_IDLE_WAIT_AXES_MOVING	11029	<p>Commanded SMC_GroupWait while axes were moving independently from the axis group (single axis movement or similar).</p> <p>在轴独立移动（单个轴移动或类似情况）时，执行了 SMC_GroupWait 命令。</p>
SMC_AXIS_INVERSE_TRANSFORMATION_EXCEEDING_POSLIMITS	11030	<p>Inverse transformation lead to axis values exceeding the configured limits.</p> <p>逆变换导致轴值超出配置限制。</p>
SMC_AXIS_GROUP_CANNOT_ADD_SAME_AXIS	11031	<p>Prohibit adding the same axis to an axis group twice</p> <p>禁止将同一轴添加到轴组两次。</p>
SMC_AXIS_GROUP_TRANSFORMATION_NOT_SET	11032	<p>No transformation is set.</p> <p>未设置任何变换。</p>
SMC_AXIS_GROUP_NON_RESUMABLE_ERROR	11033	<p>The path cannot be resumed after the current axis group error.</p> <p>当前轴组错误后无法继续路径。</p>

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_CONTINUE_DATA_NOT_WRITTEN	11034	<p>The continue data for MC_GroupContinue has not been written correctly. (MC_GroupInterrupt not called / non-resumable axis group error)</p> <p>MC_GroupContinue 的继续数据未正确写入。（未调用 MC_GroupInterrupt / 非可继续的轴组错误）</p>
SMC_AXIS_GROUP_INVALID_INTERRUPT_POSITION	11036	<p>The commanded interrupt position is invalid.</p> <p>指令中断位置无效。</p>
SMC_RELATIVE_MOVEMENT_TRACKING_CS	11037	<p>The commanded relative movement is not supported. Its start position (end position of preceding movement) and distance are given in two different coordinate systems (CS) with at least one being dynamic</p> <p>指令相对运动不受支持。其起始位置（前一个运动的结束位置）和距离在不同的坐标系（CS）中给出，其中至少有一个是动态的。</p>
SMC_RELATIVE_MOVEMENT_ABORTING_TRACKING	11038	<p>The commanded relative movement is not supported. It is Aborting and aborts a - track-in (from a static CS to a dynamic CS), - track-out (from a dynamic CS to a static CS) or - re-track (from a dynamic CS to another dynamic CS) movement.</p> <p>指令的相对运动不受支持。它将中止并中止 - 跟踪进入（从静态 CS 到动态 CS）、- 跟踪退出（从动态 CS 到静态 CS）或 - 重新跟踪（从动态 CS 到另一个动态 CS）运动。</p>
SMC_CIRCULAR_MOVEMENT_TRACKING_CS	11039	<p>The commanded circular movement is not supported. Its start position (end position of preceding movement) and target position are given in two different coordinate systems (CS) with at least one being dynamic.</p> <p>指令的圆周运动不受支持。其起始位置（前一个运动的结束位置）和目标位置在不同的坐标系（CS）中给出，其中至少有一个是动态的。</p>
SMC_CIRCULAR_MOVEMENT_ABORTING_TRACKING_CS	11040	<p>The commanded aborting circular movement is not supported. Its start position (current position) and target position are given in two different coordinate systems (CS) with at least one being dynamic, or the aborted movement is PTP tracking.</p> <p>指令的中止圆周运动不受支持。其起始位置（当前位置）和目标位置在不同的坐标系（CS）中给出，其中至少有一个是动态的，或者中止的运动是 PTP 跟踪。</p>

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_CONTINUE_POSITION_WRONG_CHECKSUM	11041	<p>The checksum of the continue position is wrong. The continue position either was not written by MC_GroupInterrupt, was modified afterwards, or an online change was executed when the continue position was still in use. Please note: The checksum is only checked when the continue position cannot be expressed as a constant value, because it changes with time (e.g. when a track in movement should be continued).</p> <p>继续位置的校验和错误。继续位置要么不是由 MC_GroupInterrupt 写入的，要么之后被修改过，或者当继续位置仍在使用时执行了在线更改。请注意：校验和仅在继续位置不能表示为常量值时才进行检查，因为它会随时间变化（例如，当应该继续跟踪进入运动时）。</p>
SMC_CIRCULAR_TRACKING_TOOL_CHANGE_NOT_SUPPORTED	11042	<p>A circular movement with a tool change is only supported in a static coordinate system.</p> <p>一个带有工具更换的圆周运动仅在静态坐标系中受支持。</p>
SMC_AXIS_GROUP_COULD_NOT_WRITE_CONTINUE_DATA	11043	<p>Continue data could not be written. This can happen when trying to write continue data while moving to another continue position.</p> <p>继续数据无法写入。这发生在尝试在移动到另一个继续位置时写入继续数据时。</p>
SMC_MODULE_AXIS_FOR_NON_ROTARY_JOINT	11044	<p>A modulo axis is not allowed for joints of the kinematics that are not rotary.</p> <p>非旋转运动学关节不允许使用模轴。</p>
SMC_MODULE_AXIS_FOR_LIMITED_ROTARY_JOINT	11045	<p>A modulo axis is not allowed for rotary joints that have a limited range. (The range comes from the kinematic transformation.)</p> <p>具有有限范围的旋转关节不允许使用模轴。（范围来自运动学变换。）</p>
SMC_MODULE_AXIS_PERIOD_NOT_360	11046	<p>A modulo axis for a rotary joint must have modulo period 360.</p> <p>一个旋转关节的模轴必须具有 360 度的模数周期。</p>
SMC_FB_WAS_NOT_CALLED_DURING_EXECUTION	11047	<p>The FB was not called for at least one cycle</p> <p>FB 在至少一个周期内未被调用</p>

Name 名称	Initial 初始	Comment 注释
SMC_NO_EVALUATION_POSSIBLE_FOR_TIME_OFFSET	11048	The value could not be evaluated for the given time offset. 在给定的时间偏移下无法评估该值。
SMC_INVALID_SOURCE_TYPE_FOR_TIME_OFFSET	11049	Values with time offset can only be evaluated for source type set. 带时间偏移的值只能针对设置的源类型进行评估。
SMC_INVALID_TIME_OFFSET	11050	Invalid time offset. Must be >=0. 无效的时间偏移量。必须 >=0。
SMC_TIME_OFFSET_TOO_LARGE	11051	The time offset is too large (larger than the forecast duration, see SMC_TuneCPKernel.fPlanningForecastDuration). 时间偏移量过大（大于预测持续时间，请参考 SMC_TuneCPKernel.fPlanningForecastDuration）。
SMC_AXIS_GROUP_MAX_NUM_ADDITIONAL_AXES_EXCEEDED	11052	More than the maximum number of additional axes where added to the axis group. The maximum number of additional axes can be increased by changing the library parameter <code>MAX_NUM_ADDITIONAL_AXES</code> in <code>SM3_CPKernelDefaults</code> . 添加到轴组中的附加轴数量超过最大值。可以通过更改库参数 <code>MAX_NUM_ADDITIONAL_AXES</code> in <code>SM3_CPKernelDefaults</code> 来增加附加轴的最大数量。
SMC_INVALID_COORD_SYSTEM_FOR_TIME_OFFSET	11053	Values with time offset cannot only be evaluated for this coordinate system. 带时间偏移量的值只能为此坐标系进行评估。
SMC_KERNEL_PTP_INTERNAL_ERROR	11100	Internal error in the kernel 内核内部错误
SMC_KERNEL_PTP_INVALID_TASKCYCLETIME	11101	Task cycle time not positive 任务周期时间不是正数
SMC_TRAFO_INVALID_PARAMETERS	12000	The parameter values of the transformation are invalid. 变换的参数值无效。

Name 名称	Initial 初始	Comment 注释
SMC_TRAFO_INVALID_CONSTELLATION	12001	<p>The requested position is outside of the working area of the transformation.</p> <p>请求的位置在变换的工作区域之外。</p>
SMC_TRAFO_INVALID_COUPLING	12002	<p>The orientation part cannot work together with the position part of the kinematics. Either, the position part doesn't implement ISMPositionKinematics2, or the orientation cannot deal with the position part's image of orientations.</p> <p>方向部分无法与运动学中的位置部分协同工作。要么，位置部分未实现ISMPositionKinematics2，要么，方向部分无法处理位置部分的方向图像。</p>
SMC_TRAFO_NOT_INITIALIZED	12003	<p>The FB implements ISMKinematicWithInitialization, but hasn't been Initialized yet.</p> <p>FB 实现了 ISMKinematicWithInitialization，但尚未初始化。</p>
SMC_TRAFO_NO_TOOL_WITH_OFFSET_ALLOWED	12004	<p>Special error for positioning part of Kin_4Axis_Palletizer, which implements ISMPositionKinematics_Offset2, but cannot actually cope with offsets <> 0.</p> <p>针对Kin_4Axis_Palletizer定位部分的特殊错误，该部分实现了ISMPositionKinematics_Offset2，但实际上无法处理偏移量<>0的情况。</p>
SMC_AXIS_GROUP_TOOL_OFFSET_INCOMPATIBLE_WITH_KINEMATICS	12005	<p>The configured tool offset is not compatible with the kinematics used</p> <p>配置的工具偏移量与所使用的运动学不兼容。</p>
SMC_TRAFO_INVALID_AXIS_LIMITS	12006	<p>The configured position limits of one or more axes are not valid for the kinematics.</p> <p>一个或多个轴的配置位置限制对运动学无效。</p>
SMC_AXIS_GROUP_PATH_DEVIATION_TOO_HIGH	12007	<p>This error code has been replaced by SMC_AXIS_GROUP_MAX_AXIS_LAG_EXCEEDED, SMC_AXIS_GROUP_MAX_POSITION_LAG_EXCEEDED and SMC_AXIS_GROUP_MAX_ORIENTATION_LAG_EXCEEDED.</p> <p>此 错误代码已被 SMC_AXIS_GROUP_MAX_AXIS_LAG_EXCEEDED、SMC_AXIS_GROUP_MAX_POSITION_LAG_EXCEEDED 和 SMC_AXIS_GROUP_MAX_ORIENTATION_LAG_EXCEEDED 替代。</p>

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_POSITION_EXCEEDS_POSITION_LIMITS	12008	The given axis position exceeds the position limits of an axis. 给定的轴位置超出了轴的位置限制。
SMC_AXIS_GROUP_NO_DYNAMIC_MODEL_CONFIGURED	12009	No dynamic model has been configured for the axis group. 轴组未配置动态模型。
SMC_DYNAMICS_NUM_TORQUES_NEQUAL_NUM_AXES	12010	The number of torques returned by the dynamic model is different from the number of axes. 返回的动态模型扭矩数量与轴数量不同。
SMC_AXIS_GROUP_MAX_AXIS_LAG_EXCEEDED	12020	The axis lag is higher than the allowed tolerance. When tracking is used, this indicates that the tracked object is accelerating/ decelerating too quickly for the robot to follow. See SMC_SetPathTolerance . 轴滞后高于允许的公差。在使用跟踪时，这表示被跟踪物体加速/减速太快，机器人无法跟随。参见 SMC_SetPathTolerance 。
SMC_AXIS_GROUP_MAX_POSITION_LAG_EXCEEDED	12021	The position lag of the TCP is higher than the allowed tolerance. When tracking is used, this indicates that the tracked object is accelerating/ decelerating too quickly for the robot to follow. See SMC_SetPathTolerance . TCP 的位置滞后高于允许的公差。在使用跟踪时，这表示被跟踪物体加速/减速太快，机器人无法跟随。参见 SMC_SetPathTolerance 。
SMC_AXIS_GROUP_MAX_ORIENTATION_LAG_EXCEEDED	12022	The orientation lag of the TCP is higher than the allowed tolerance. When tracking is used, this indicates that the tracked object is accelerating/ decelerating too quickly for the robot to follow. See SMC_SetPathTolerance . TCP 的方向滞后高于允许的公差。在使用跟踪时，这表示被跟踪物体加速/减速太快，机器人无法跟随。参见 SMC_SetPathTolerance 。
SMC_CP_CACHE_FULL	12100	The cache of the CP planner is too small. CP 规划器的缓存太小。
SMC_CP_EVAL_ERROR	12101	The evaluation of the position on a path element failed (internal error). 在路径元素上的位置评估失败（内部错误）。

Name 名称	Initial 初始	Comment 注释
SMC_CP_NO_N_CONTINUABLE_STATE	12102	Non-continuable state reached (internal error). 达到不可继续状态（内部错误）。
SMC_CP_MAX_LENGTH_EXCEEDED	12103	Maximum trajectory length exceeded (internal error). 最大轨迹长度超出（内部错误）。
SMC_CP_ACCELERATION_TOO_HIGH	12104	Path acceleration too high (invalid state, internal error). 路径加速过高（无效状态，内部错误）。
SMC_CP_MAX_ITERATIONS_EXCEEDED	12105	Maximum number of iterations exceeded (internal error). 迭代次数超过最大值（内部错误）。
SMC_CP_NO_TRAJECTORY	12106	No trajectory could be computed (internal error). 无法计算轨迹（内部错误）。
SMC_CP_OUT_QUEUE_FULL	12107	The out-queue is full (internal error). 输出队列已满（内部错误）。

Name 名称	Initial 初始	Comment 注释
SMC_CP_QUEUE_UNDERRUN	12108	<p>The computation of the trajectory could not be performed in real time. The fill level of the sync buffer between the planning task and the bus task was too low.</p> <p>轨迹计算无法实时执行。规划任务与总线任务之间的同步缓冲区填充水平过低。</p> <p>Possible reasons:</p> <ul style="list-style-type: none">• The task configuration of the planning task is not set correctly. Please see the online help chapter “Diagnosis of Problems with Movements” for good settings. 规划任务的配置不正确。请参阅在线帮助章节“运动问题诊断”以获取正确的设置。• The performance of the PLC is not sufficient. Possible measures to avoid the error: PLC 的性能不足。避免错误的可能措施：<ul style="list-style-type: none">◦ use a separate, dedicated CPU core for the planning task 为规划任务使用一个单独的专用 CPU 核心◦ increase the bus task interval 增加总线任务间隔◦ increase the planning interval and/or the sync buffer duration using SMC_TuneCPKernel 使用 SMC_TuneCPKernel 增加规划间隔和/或同步缓冲区持续时间 <p>The current fill level of the sync buffer can be monitored using the CurrentSyncBufferDuration output of MC_GroupReadStatus. 可以使用 CurrentSyncBufferDuration 的 MC_GroupReadStatus 输出监控同步缓冲区的当前填充水平</p>
SMC_CP_INVALID_QUEUE	12109	<p>Invalid queue (invalid size or pointer)</p> <p>无效队列（无效大小或指针）</p>
SMC_CP_BLENDING_INTERNAL_ERROR	12110	<p>An internal error occurred while blending two CP movements</p> <p>在混合两个 CP 运动时发生了内部错误</p>
SMC_CP_CIRCULAR_POINTS	12111	<p>The three points that define the circle are collinear.</p> <p>定义圆的三点共线。</p>

Name 名称	Initial 初始	Comment 注释
SMC_CP_CIRCLE_CENTER_NOT_ON_BISector	12112	The center point is not on the perpendicular bisector of the start and end point. 中心点不在起点和终点之间的垂直平分线上。
SMC_CP_CIRCLE_RADIUS_ZERO	12113	The radius is zero 半径为零
SMC_CP_CIRCLE_DISTANCE_LARGER_THAN_DIAMETER	12114	The distance between start and end point is larger than the diameter. (When trying to create a circle using <code>SMC_Circ_Mode.Radius</code> .) 起始点和终点之间的距离大于直径。（当尝试使用 <code>SMC_Circ_Mode.Radius</code> 创建圆时。）
SMC_CP_CIRCLE_START_AND_ENDPOINT_EQUAL	12115	The start and end point are equal (<code>SMC_Circ_Mode.Radius</code>). 起始点和终点相等（ <code>SMC_Circ_Mode.Radius</code> ）。
SMC_CP_BLENDING_DEGENERATE_SPLINE	12116	The blending spline is degenerate (too short or non-regular) 混合样条退化（太短或不规则）
SMC_CP_ELEMENT_TOO_SHORT	12117	The path element cannot be created because it is too short. 路径元素无法创建，因为它太短。
SMC_CP_COULD_NOT_CUT_PATH	12118	The path could not be cut for aborting movement (internal error). 路径无法中断移动（内部错误）。
SMC_CP_INVALID_ANGULAR_VELOCITY_ACCELERATION	12119	The given angular velocity or acceleration is invalid (quaternion with non-zero real part, internal error). 给定的角速度或加速度无效（实部非零的四元数，内部错误）。
SMC_CP_INVALID_ORIENTATION	12120	The given orientation is invalid (non-orthonormal matrix or non-unit quaternion, internal error). 给定的方向无效（非正交矩阵或非单位四元数，内部错误）。
SMC_CP_TIME_BUDGET_EXCEEDED	12121	The given time budget for the computation is exceeded (internal error). 计算的时间预算已超出（内部错误）。

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_AXIS_LIMIT_VIOLATED	12122	<p>A limit of an axis has been violated. This can happen if a CP movement is done too close to a singularity or if the path has a very high curvature.</p> <p>轴的限制已被违反。这可能是由于 CP 运动过于接近奇点，或者路径具有非常高的曲率。</p>
SMC_CP_CONFIG_DIFFER	12125	<p>The kinematic configuration of the start position differs from the end position. The CP movement would pass a singularity.</p> <p>起始位置的运动学配置与结束位置不同。CP 运动将经过奇点。</p>
SMC_CP_BUS_TASK_NOT_CALLED	12126	<p>This error is obsolete and is maintained only for compatibility. If a CP-halt/-stop is commanded, some information has to be transferred to the bus task. We expect this to happen before the next cycle of the slow task.</p> <p>此错误已过时，仅保留以兼容。如果命令 CP 停止，必须将一些信息传输到总线任务。我们期望这发生在慢任务的下个周期之前。</p>
SMC_CP_NO_ROOT_IN_INTERVAL_FOUND	12127	<p>The stop trajectory could not be found in the interval. (internal error)</p> <p>在指定间隔内未找到停止轨迹。（内部错误）</p>
SMC_CP_KIN_DOES_NOT_SUPPORT_AXIS_ORIENTATION_IPO	12128	<p>The kinematics does not support the orientation mode “Axis” for continuous path movements.</p> <p>运动学不支持连续路径运动中的“轴”方向模式。</p>
SMC_CP_AXIS_ORIENTATION_IPO_NOT_SUPPORTED_FOR_CPTR	12129	<p>The axis orientation interpolation mode is not supported for CP movements with a dynamic PCS (tracking).</p> <p>对于具有动态 PCS（跟踪）的 CP 运动，轴方向插补模式不受支持。</p>
SMC_CP_INVALID_PATH_ELEMENT	12130	<p>An invalid path element has been created (internal error)</p> <p>创建了一个无效的路径元素（内部错误）</p>
SMC_CP_TRANSITION_NOT_SMOOTH	12131	<p>The transition between two path elements is not G2 continuous, and there is no stop (internal error)</p> <p>两个路径元素之间的过渡不是 G2 连续，并且没有停止（内部错误）</p>

Name 名称	Initial 初始	Comment 注释
SMC_CP_AXIS_ORIENTATION_IPO_CONFIG_DIFFERS	12132	<p>Axis orientation interpolation mode is used, but between the start end end position, there is a singularity of the position kinematics.</p> <p>使用了轴方向插补模式，但在起始位置和结束位置之间，位置运动学存在奇点。</p>
SMC_CP_AXIS_ORIENTATION_OFFSET2_NOT_IMPLEMENTED	12133	<p>The position kinematics has configurations but does not implement the interface ISMPositionKinematics_Offset2. In this case, axis orientation interpolation is not possible.</p> <p>位置运动学具有配置但没有实现接口 ISMPositionKinematics_Offset2。在这种情况下，轴方向插补不可用。</p>
SMC_CP_ROTARY_AXIS_PERIOD_MISMATCH	12134	<p>The target position of a rotary axis will not be reached in the commanded period. (E.g. the commanded target position is -170°, but the target will be reached with position 190° instead.) This means that the chosen interpolation to the target position is not compatible with the commanded position. For PTP movements (MC_MoveDirect*), this error can happen if the previous movement is a CP movement (MC_MoveLinear*, MC_MoveCircular*), and if the CP movement is very long. To avoid the problem, the CP movement should be divided into two or more shorter movements. The problem can occur if a rotary axis has to move 360° or more during the CP movement.</p> <p>旋转轴的目标位置在指令周期内无法达到。（例如，指令目标位置为-170°，但目标位置将用 190°达到。）这意味着所选的目标位置插补方式与指令位置不兼容。对于 PTP 运动（MC_MoveDirect*），如果前一个运动是 CP 运动（MC_MoveLinear*，MC_MoveCircular*），并且 CP 运动时间过长，可能会发生此错误。为避免问题，应将 CP 运动分成两个或多个较短的运动。如果旋转轴在 CP 运动期间需要移动 360° 或更多，可能会出现此问题。</p>
SMC_CP_ROTARY_AXIS_RANGE_VIOLATION	12135	<p>A rotary axis has violated the allowed axis range during a CP movement. The CP movment is not in the working area.</p> <p>旋转轴在 CP 运动期间违反了允许的轴范围。CP 运动不在工作区域。</p>
SMC_CP_COMPUTE_TARGET_DISCONTINUITY	12136	<p>The target trajectory could not be computed due to a discontinuity of the end position (internal error).</p> <p>目标轨迹无法计算，因为终点位置存在不连续性（内部错误）。</p>
SMC_CP_TRAJECTORY_NOT_SMOOTH	12137	<p>The trajectory is not smooth, the phase end states do not equal the the current state (internal error).</p> <p>轨迹不平滑，阶段结束状态不等于当前状态（内部错误）。</p>

Name 名称	Initial 初始	Comment 注释
SMC_CP_ERROR_CREATING_PARAM_TRANSFORM	12138	A parameter transformation could not be created (internal error). 无法创建参数转换（内部错误）。
SMC_CP_PTP_DATA_NUMBER_OF_AXES	12139	Error generating path-invariant PTP element (internal error). 生成路径不变 PTP 元素时出错（内部错误）。
SMC_CP_NEGATIVE_PATH_VELOCITY	12140	Error while computing a new trajectory: the path velocity after phase 1 (positive jerk of length dTau1) is negative (internal error). 计算新轨迹时出错：阶段 1 后的路径速度（长度为 dTau1 的正加速度）为负（内部错误）。
SMC_CP_TRANSITIONING_FROM_SINGLE_AXIS_MOVEMENT_NOT_SUPPORTED	12141	Transitioning from a single axis movement to a continuous path movement is not supported. 不支持从单轴运动过渡到连续路径运动。
SMC_CP_PLANNER_NO_PROGRESS	12142	The CP-planner did not make any progress. This is an internal error That can be triggered by very sharp corners (e.g. blending between short elements or with small corner distance). CP-planner 没有任何进展。这是一个内部错误，可能由非常尖锐的角落触发（例如，在短元素之间或与小角落距离之间进行混合）。
SMC_CP_INTERNAL_EVAL_CACHE_ERROR	12143	Internal error in the evaluation cache of the CP-planner. CP-planner 的评估缓存中存在内部错误。
SMC_CP_INVALID_ROOT_ACC_TOO_HIGH	12144	The acceleration at the trajectory end is too high for a valid root (internal error). 轨迹末端的加速度对于有效的根来说太高（内部错误）。
SMC_CP_INVALID_ROOT_TRAJECTORY_TOO_LARGE	12145	The stop trajectory is too large. Reduce the velocity or increase the acceleration and jerk limits. 停止轨迹太大。降低速度或增加加速度和加加速度限制。
SMC_CP_EMPTY_TRAJECTORY	12146	The trajectory is empty, i.e. has no phases (internal error). 轨迹为空，即没有阶段（内部错误）。

Name 名称	Initial 初始	Comment 注释
SMC_CP_FORECAST_TOO_LARGE	12147	<p>The forecast duration is too large given the configured planning interval and sync buffer duration. To avoid this error, either reduce the forecast duration, reduce the sync buffer duration, or increase the planning interval. See SMC_TuneCPKernel for more details.</p> <p>根据配置的计划间隔和同步缓冲持续时间，预测持续时间过大。为避免此错误，请减少预测持续时间、减少同步缓冲持续时间或增加计划间隔。有关详细信息，请参阅 SMC_TuneCPKernel。</p>
SMC_CP_INVALID_ROOT_ENDPOS_NOT_GREATER_STARTPOS	12148	<p>The end position of the trajectory is not greater than the start position (internal error).</p> <p>轨迹的结束位置不大于起始位置（内部错误）。</p>
SMC_CP_AXIS_VELOCITY_LIMIT_EXCEEDED_WITHOUT_MOVING	12150	<p>Axis velocity limit exceeded without moving on the path.</p> <p>在路径上未移动时，轴速度限制已超出。</p>
SMC_CP_AXIS_ACCELERATION_LIMIT_EXCEEDED_WITHOUT_MOVING	12151	<p>Axis acceleration limit exceeded without moving on the path.</p> <p>轴加速度限制超出，且未在路径上移动。</p>
SMC_CP_AXIS_JERK_LIMIT_EXCEEDED_WITHOUT_MOVING	12152	<p>Axis jerk limit exceeded without moving on the path.</p> <p>轴加加速度限制超出，且未在路径上移动。</p>
SMC_CP_AXIS_TORQUE_LIMIT_EXCEEDED_WITHOUT_MOVING	12153	<p>Axis torque/force limit exceeded without moving on the path.</p> <p>轴扭矩/力限制超出，且未在路径上移动。</p>
SMC_GROUPJOG2_MAX_DISTANCE_NON_POSITIVE	12200	<p>Either MaxLinearDistance or MaxAngularDistance of SMC_GroupJog2 is non-positive.</p> <p>SMC_GroupJog2 的 MaxLinearDistance 或 MaxAngularDistance 为非正数。</p>

Name 名称	Initial 初始	Comment 注释
SMC_GROUPJOG2_DYNAMIC_CS_NOT_SUPPORTED	12201	SMC_GroupJog2 does not support jogging in dynamic coordinate systems. SMC_GroupJog2 不支持在动态坐标系中进行点动。
SMC_TRIGGER_TOO_MANY_TRIGGERS_PREPARED	12300	Too many triggers have been prepared for the next movement. 为下一次运动准备的触发器过多。
SMC_TRIGGER_UNSUPPORTED_MOVEMENT_TYPE	12301	Triggers for wait commands and for halt/stop commands are not supported. 等待命令和停止/暂停命令的触发器不受支持。
SMC_TRIGGER_INVALID_POSITION_TYPE	12302	The given trigger position type is not valid. 给定的触发器位置类型无效。
SMC_TRIGGER_RELATIVE_POSITION_OUT_OF_RANGE	12303	The relative trigger position must be in the range [-1, 1]. 相对触发位置必须在 [-1, 1] 范围内。
SMC_TRIGGER_PLANE_NORMAL_NOT_A_UNIT	12304	The normal vector for a trigger plane must be a unit-vector. 触发平面的法向量必须是一个单位向量。
SMC_TRIGGER_PLANE_DISTANCE_NEGATIVE	12305	The distance of the trigger plane must be non-negative. 触发平面的距离必须是非负的。
SMC_TRIGGER_PLANE_COORD_SYSTEM_INVALID	12306	The coordinate system of the trigger plane must not be ACS or TCS. 触发平面的坐标系不能是 ACS 或 TCS。
SMC_TRIGGER_DISTANCE_OUT_OF_RANGE	12307	The trigger distance must be in the range [-len, len], where len is the length of the movement. 触发距离必须在 [-len, len] 范围内，其中 len 是移动的长度。
SMC_TRIGGER_PLANE_NO_INTERSECTION	12308	No intersection between the trigger plane and the movement. 触发平面与移动之间没有交集。

Name 名称	Initial 初始	Comment 注释
SMC_TRIGGER_TRACKING_TRANSITION_NOT_SUPPORTED	12309	Triggers not supported for tracking movements between different coordinate systems. 不支持在不同坐标系之间跟踪移动的触发器。
SMC_TRIGGER_PTP_NOT_SUPPORTED	12310	Triggers with position type MvtDistance and PlaneIntersection are not supported for PTP movements. 具有位置类型 MvtDistance 和 PlaneIntersection 的触发器不支持用于 PTP 移动。
SMC_CAM_BUILDER_FULL	12400	The cam builder is full. No new cam segments can be added. 凸轮构建器已满。无法添加新的凸轮段。
SMC_CAM_BUILDER_INVALID_MASTER_DISTANCE	12401	The master distance of a cam segment must be > 0. 凸轮段的基准距离必须 > 0。
SMC_CAM_BUILDER_GAP_BETWEEN_SEGMENTS	12402	The new segment does not connect to the master end position of the previous segment. 新段无法与前一段的主端位置连接。
SMC_CAM_BUILDER_NO_IMPLICIT_LEFT_BOUNDARY_ALLOWED	12403	No implicit left boundary allowed, because the last segment has an implicit right boundary. 不允许隐式左边界，因为最后一段有一个隐式右边界。
SMC_CAM_BUILDER_INVALID_IMPLICIT_CAM_SEGMENT_MASTER_DISTANCE	12404	x0 of the new segment results in a master distance <=0 for the previous implicit segment. 新片段的 x0 导致前一个隐式片段的主距离<=0。
SMC_CAM_BUILDER_CAM_REF_INSUFFICIENT_MEMORY	12405	The cam builder has more segments than the MC_CAM_REF can store. 凸轮构建器拥有的片段比 MC_CAM_REF 可以存储的更多。

Name 名称	Initial 初始	Comment 注释
SMC_CAM_BUILDER_LAST_SEGMENT_HAS_IMPLICIT_RIGHT_BOUNDARY	12406	The last segment has an implicit right boundary. 最后一个片段有一个隐式右边界。
SMC_CAM_BUILDER_INVALID_CAM_REF_INITIALIZATION	12407	MC_CAM_REF init error, due to a null pointer to the cam segments. MC_CAM_REF 初始化错误，由于指向凸轮片段的空指针。
SMC_CAM_BUILDER_ERROR_PENDING	12408	The data of the cam builder cannot be written to the MC_CAM_REF, because an error is pending. cam 构建器的数据无法写入 MC_CAM_REF，因为存在待处理的错误。
SMC_CAM_BUILDER_CONTINUITY_REQUIREMENT_VIOLATED	12409	The continuity check of the cam builder detected a violated continuity requirement. cam 构建器的连续性检查检测到违反了连续性要求。
SMC_CAM_BUILDER_MASTER_DISTANCE_TOO_SHORT	12410	The master distance of the cam segment is too short. cam 段的基准距离太短。
SMC_CAM_BUILDER_IMPLICIT_CAM_SEGMENT_DISTANCE_TOO_SHORT	12411	The master distance of the previous implicit segment is too short. 前一个隐式段的基准距离太短。
SMC_CAM_BUILDER_CAM_REF_INVALID_ARRAY_SIZE	12412	Array size is limited to 32767 SMC_CAM_SEGMENT entries and must be a multiple of this data type. 数组大小限制为 32767 个 SMC_CAM_SEGMENT 条目，并且必须是此数据类型的倍数。
SMC_CAM_BUILDER_MODIFIED_SINE_INVALID_LAMBDA_OR_ACC_PARAM	12415	The given lambda or acceleration parameter Ca* of this segment is invalid. 此段的给定 lambda 或加速参数 Ca*无效。

Name 名称	Initial 初始	Comment 注释
SMC_CAM_B UILDER_MODIFIED_SINE_A CC_PARAM_R IGHT_BOUND _IMPLICIT	12416	A modified sine segment defined by the acceleration parameter Ca* must not have an implicit right boundary. 由加速参数 Ca*定义的修改正弦段不得具有隐式右侧边界。
SMC_CAM_B UILDER_INVALID_COMPILE _TYPE	12417	MC_CAM_REF has an unsupported compile type. MC_CAM_REF 具有不支持的编译类型。
SMC_MOVEM ENT_INTERN AL_ERROR	13001	Internal error in a movement. 运动中的内部错误。
SMC_MOVEM ENT_GET_PO S_INTERNAL_ ERROR	13002	Internal error while trying to get a position in a movement. 尝试在运动中获取位置时发生内部错误。
SMC_CPTR_I NTERNAL_ER ROR	13003	Internal error in the CPTR kernel. CPTR 内核中的内部错误。
SMC_CP_IPO_ INTERNAL_ER ROR	13004	Internal error while interpolating in the CP kernel. CP 内核插值时发生内部错误。
SMC_CP_ADD _NEW_MOVE MENT_INTER NAL_ERROR	13005	Internal error while adding a new movement to the CP kernel. 在向 CP 内核添加新运动时发生内部错误。
SMC_AXIS_G ROUP_COORD INATION_INT ERNAL_ERRO R	13006	Internal error while coordinating kernels. 在协调内核时发生内部错误。
SMC_AXIS_G ROUP_ADD_M OVEMENT_IN TERNAL_ERR OR	13007	Internal error while adding movements to the axis group. 在向轴组添加运动时发生内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_AXIS_GROUP_READ_AXIS_STATES_INTERNAL_ERROR	13008	Internal error while reading the state of one of the group's axes. 在读取组中一个轴的状态时发生内部错误。
SMC_AXIS_GROUP_READ_VELOCITY_INTERNAL_ERROR	13009	Internal error while trying to read the velocity. 读取速度时发生内部错误。
SMC_AXIS_GROUP_READ_ACCELERATION_INTERNAL_ERROR	13010	Internal error while trying to read the acceleration. 读取加速度时发生内部错误。
SMC_AXIS_GROUP_INVALID_STATE_INTERNAL_ERROR	13011	Internal error: The axis group is in an invalid state. 内部错误：轴组处于无效状态。
SMC_AXIS_GROUP_PCS_INTERNAL_ERROR	13012	Internal error while handling a PCS. 处理 PCS 时发生内部错误。
SMC_AXIS_GROUP_INTERRUPT_INTERNAL_ERROR	13013	An internal error occurred during an interrupt. 在发生中断时出现内部错误。
SMC_CONTINUE_DATA_READ_INTERNAL_ERROR	13014	Internal error while reading continue data. 读取继续数据时出现内部错误。
SMC_CONTINUE_DATA_WRITE_INTERNAL_ERROR	13015	Internal error while writing continue data. 写入继续数据时出现内部错误。
SMC_PATH_ELEMENT_INTERNAL_ERROR	13016	Internal error in a path element. 路径元素中出现内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_PATH_ELEMENT_ESTIMATE_LIMITS_INTERNAL_ERROR	13017	Internal error while estimating the limits of a path element. 在估计路径元素的极限时发生内部错误。
SMC_PATH_ELEMENT_ZERO_LENGTH_INTERNAL_ERROR	13018	Internal error in a zero-length path element. 在长度为零的路径元素中发生内部错误。
SMC_PATH_ELEMENT_BLEND_INTERNAL_ERROR	13019	Internal error in a blending element. 在混合元素中发生内部错误。
SMC_PATH_ELEMENT_BLEND_GEOMETRIC_INTERNAL_ERROR	13020	Internal error in the geometric part of a path element. 在路径元素的几何部分发生内部错误。
SMC_PATH_ELEMENT_BLEND_ORIENTATION_INTERNAL_ERROR	13021	Internal error in the orientation part of a path element. 路径元素的方向部分出现内部错误。
SMC_PATH_ELEMENT_BLEND_AXIS_SPACE_INTERNAL_ERROR	13022	Internal error in an axis space element. 轴空间元素出现内部错误。
SMC_ELEMENT_FUNCTION_CARTESIAN_INTERNAL_ERROR	13023	Internal error in an element function. 元素函数出现内部错误。
SMC_CP_HOLD_STOP_INTERNAL_ERROR	13024	Internal error during cp halt or stop. 在 cp 停止或暂停期间出现内部错误。
SMC_TRJ_PLANNING_INITIALIZATION_INTERNAL_ERROR	13025	Internal error while initializing trajectory planning. 初始化轨迹规划时发生内部错误。
SMC_TRJ_PLANNING_GENERATION_SAMPLES_INTERNAL_ERROR	13026	Internal error while generating samples. 生成样本时发生内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_TRJ_PLANNING_PATH_OUT_INTERNAL_ERROR	13027	Internal error while creating the output path. 创建输出路径时发生内部错误。
SMC_TRJ_PLANNING_EVAL_AXIS_INTERNAL_ERROR	13028	Internal error while evaluating axis values. 评估轴值时发生内部错误。
SMC_TRJ_PLANNING_LOOKAHEAD_INTERNAL_ERROR	13029	Internal error in planning lookahead. 规划前瞻中出现内部错误。
SMC_AXIS_GROUP_READ_JERK_INTERNAL_ERROR	13030	Internal error while trying to read the jerk. 尝试读取 jerk 时出现内部错误。
SMC_AXIS_GROUP_WRITE_CONTINUE_POS_INTERNAL_ERROR	13031	Internal error while writing the continue position. 写入继续位置时出现内部错误。
SMC_CP_TRANSITION_CHECK_FAILED	13032	Internal error while checking whether the path is continuous. 检查路径是否连续时出现内部错误。
SMC_ABORTING_INTERNAL_ERROR	13033	Internal error while aborting. 内部错误发生在中止过程中。
SMC_LINE_TO_REL_STANDSTILL_INTERNAL_ERROR	13034	Internal error while creating a line to relative standstill. 内部错误发生在创建一条到相对静止状态的路径时。
SMC_PATH_ELEMENT_POSE_EVAL_INTERNAL_ERROR	13035	Internal error while evaluating a pose on a path element. 内部错误发生在评估路径元素上的姿态时。
SMC_CS_REFERENCE_COUNT_INTERNAL_ERROR	13036	Internal error in coordinate system reference counting. 坐标系引用计数中的内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_PATH_QUEUE_INTERNAL_ERROR	13037	Internal error in the path queue. 路径队列内部错误。
SMC_PATH_ELEMENT_INTERNAL_ERROR	13038	Internal error in the path queue. 路径队列内部错误。
SMC_ELEMENT_FUNCTION_INTERNAL_ERROR	13039	Internal error in the element function queue. 元素函数队列内部错误。
SMC_MAC_DUPLICATE_CALLER_INTERNAL_ERROR	13040	Internal error in the multi acyclic communicator due to a duplicate SDO caller. 由于重复的 SDO 调用者，多无环通信器内部错误。
SMC_MAC_INTERNAL_ERROR	13041	Internal error in the multi acyclic communicator. 多无环通信器内部错误。
SMC_READ_POSITION_INTERNAL_ERROR	13042	Internal error when reading the axis group position. 读取轴组位置时发生内部错误。
SMC_ELEMENT_PROJECT_POINT_INTERNAL_ERROR	13043	Internal error in function GeoPrim_ProjectPoint 在函数 GeoPrim_ProjectPoint 中发生内部错误。
SMC_CAM_EVAL_INTERNAL_ERROR	13044	Internal error during cam table evaluation 在 cam 表评估期间发生内部错误。
SMC_CAM_BUILDER_INTERNAL_ERROR_INVALID_CAM_SEGMENT_TYPE	13045	Internal error when evaluating the cam segment type. 在评估 cam 段类型时发生内部错误。
SMC_CAM_BUILDER_INTERNAL_ERROR_INVALID_DESCRIPTION_TYPE	13046	Internal error when evaluating the cam segment description type. 在评估 cam 段描述类型时出现内部错误。

Name 名称	Initial 初始	Comment 注释
SMC_CAM_B UILDER_INTE RNAL_ERROR _IMPLICIT_BO UNDARY_CAN NOT_BE_EVA LUATED	13047	Internal error when trying to evaluate an implicit boundary. 在尝试评估隐式边界时出现内部错误。
SMC_CAM_B UILDER_INTE RNAL_ERROR _OUT_OF_BO UNDS	13048	Internal error when trying to access cam segments out of bounds. 在尝试访问边界外的 cam 段时出现内部错误。
SMC_AXIS_M OVEMENTS_I NTERNAL_ER ROR	13070	Internal error in the axis movements. 在轴运动中出现内部错误。
SMC_STOP_I NTERNAL_ER ROR	13071	Internal error in MC_Stop. MC_Stop 内部错误。