```
//The function is :
function Decoder(bytes, port) {
// Decode an uplink message from a buffer
// (array) of bytes to an object of fields.
var latitude=0;//gps latitude,units: Â°
if(bytes[0] !== 0)
{
  latitude=(bytes[0]<<24 | bytes[1]<<16 | bytes[2]<<8 | bytes[3])/1000000;//gps latitude,units:
Â°
}
else
{
  latitude=0;//gps latitude,units: Â°
}
var longitude = 0;
if(bytes[4] !== 0)
{
  longitude=(bytes[4]<<24 | bytes[5]<<16 | bytes[6]<<8 | bytes[7])/1000000;//gps
longitude,units: Â°
}
else
{
 longitude=0;//gps longitude,units: Â°
}
var alarm=(bytes[8] & 0x40)?"TRUE":"FALSE";//Alarm status

var batV=(((bytes[8] & 0x3f) <<8) | bytes[9])/1000;//Battery,units:V
if(bytes[10] & 0xC0==0x40)
{
  var motion_mode="Move";
}
else if(bytes[10] & 0xC0 ==0x80)
{
  motion_mode="Collide";
}
else if(bytes[10] & 0xC0 ==0xC0)
```

```
{
  motion_mode="User";
}
else
{
  motion_mode="Disable";
}                                    //mode of motion
var led_updown=(bytes[10] & 0x20)?"ON":"OFF";//LED status for position,uplink and downlink
var Firmware = 160+(bytes[10] & 0x1f);  // Firmware version; 5 bits

var roll=(bytes[11]<<8 | bytes[12])/100;//roll,units: Â°

var pitch=(bytes[13]<<8 | bytes[14])/100; //pitch,units: Â°
var hdop = 0;
if(bytes[15] > 0)
{
   hdop =bytes[15]/100; //hdop,units: Â°
}
else
{
   hdop =bytes[15];
}
var altitude =(bytes[16]<<8 | bytes[17]) / 100; //Altitude,units: Â°
return {
latitude: latitude,
longitude: longitude,
roll: roll,
pitch:pitch,
battery:batV,
ALARM_status:alarm,
MD:motion_mode,
LON:led_updown,
FW:Firmware,
HDOP:hdop,
altitude:altitude,
accuracy:3
};
}
```