

# KBSW180126 Win32-

get\_laser\_scan,

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- - Visual Studio 2010 SP1
  - Slamware Windows SDK:[Slamware Windows SDK](#)
  - RoboStudio():[Robostudio installer](#)
  - Sample Code:



Visual Studio

Visual Studio 2010SP1.Net FrameworkSP1

- - Slamware SDP mini
  - Slamware Slamware
  - Apollo/Ares/Athena

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Win32-

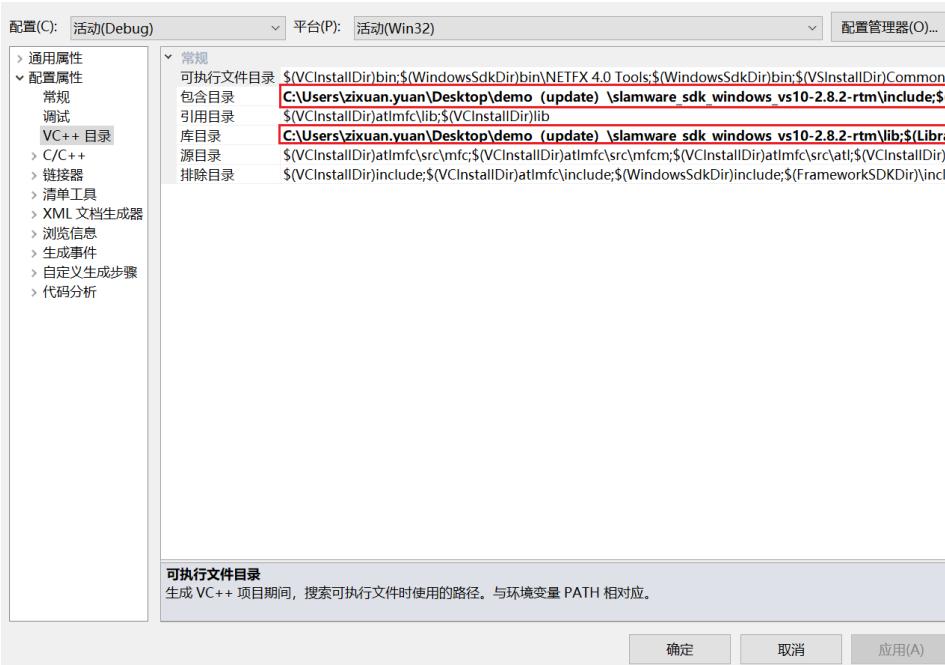
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1. samplesget\_laser\_scan, StartUp project
  - Solution 'samples' (9 projects)
    - > artifacts\_demo
    - > composite\_map\_demo
    - > configure\_network\_demo
    - > **get\_laser\_scan**
    - > get\_power\_status
    - > get\_sensor\_value
    - > go\_home\_to\_charge
    - > move\_to\_spot
    - > rotation\_action\_demo

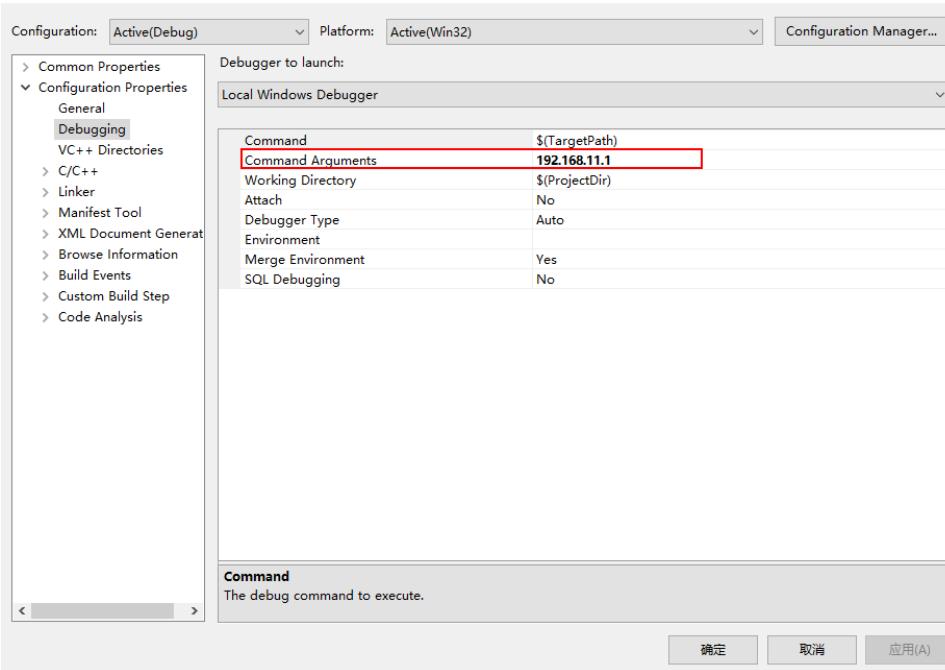
2. get\_laser\_scan, Slamware SDK includelib



Slamware SDKincludelibVisual Studio



### 3. get\_laser\_scan, Debugging command Arguments 192.168.11.1 get\_laser\_scan <IP address>



### 4. F5

5.

```
PS C:\Users\xixuan.yuan\Desktop\demo (update) \SlamwareApplicationDemos-Windows-master\Debug> .\get_laser_scan.exe 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.8.2_rtm
SDP Version: 8.2_rtm (Jun 3 2021)
Angle: 3.13784; Distance: 0.37377; is Valid: 1
Angle: 3.13345; Distance: 0.29401; is Valid: 1
Angle: 3.12881; Distance: 0.25446; is Valid: 1
Angle: 3.12466; Distance: 0.20102; is Valid: 1
Angle: 3.12027; Distance: 0.15178; is Valid: 1
Angle: 3.11587; Distance: 0.09449; is Valid: 1
Angle: 3.11173; Distance: 0.03953; is Valid: 1
Angle: 3.10757; Distance: 0.99852; is Valid: 1
Angle: 3.10294; Distance: 0.93602; is Valid: 1
Angle: 3.09854; Distance: 0.88743; is Valid: 1
Angle: 3.09414; Distance: 0.87102; is Valid: 1
Angle: 3.08998; Distance: 0.84667; is Valid: 1
Angle: 3.08558; Distance: 0.7986; is Valid: 1
Angle: 3.08143; Distance: 0.77457; is Valid: 1
Angle: 3.07703; Distance: 0.74283; is Valid: 1
Angle: 3.07263; Distance: 0.69525; is Valid: 1
Angle: 3.06823; Distance: 0.63184; is Valid: 1
Angle: 3.05681; Distance: 100000; is Valid: 0
Angle: 3.0524; Distance: 100000; is Valid: 0
Angle: 3.04838; Distance: 100000; is Valid: 0
Angle: 3.04397; Distance: 100000; is Valid: 0
Angle: 3.03965; Distance: 100000; is Valid: 0
Angle: 3.03524; Distance: 100000; is Valid: 0
Angle: 3.01744; Distance: 1.04384; is Valid: 1
Angle: 3.01302; Distance: 1.04391; is Valid: 1
Angle: 3.00884; Distance: 1.04397; is Valid: 1
Angle: 3.00439; Distance: 1.04383; is Valid: 1
Angle: 3.00022; Distance: 1.04592; is Valid: 1
Angle: 2.99576; Distance: 1.04782; is Valid: 1
Angle: 2.99135; Distance: 1.05399; is Valid: 1
Angle: 2.98814; Distance: 1.06999; is Valid: 1
Angle: 2.98368; Distance: 1.07394; is Valid: 1
```

```
SlamwareCorePlatform sdp = SlamwareCorePlatform::connect(argv[1], 1445);
std::cout << "SDK Version: " << sdp.getSDKVersion() << std::endl;
std::cout << "SDP Version: " << sdp.getSDPVersion() << std::endl;
rpos::features::system_resource::LaserScan laser_scan = sdp.getLaserScan();
std::vector<rpos::core::LaserPoint> laser_points =laser_scan.getLaserPoints();

for (std::vector<rpos::core::LaserPoint>::iterator it = laser_points.begin(); it!=
laser_points.end(); ++it)
    std::cout << "Angle: " << it->angle() << "; Distance: " <<
    it->distance() << "; is Valid: " << it->valid() << std::endl;
```