

Windows SDK sample overview(en)

General

This directory contains document of slamware demo programs, which are developed based on Slamware windows SDK

[KBSW180136 Win32 - Navigate to Target PointStandard Mode and Virtual Track Mode](#)

This document introduces the demo project of "move_to_spot", including how to move in standard mode and virtual track mode.

[KBSW180137 Win32- Recover Localization](#)

This document introduces the demo project of "recover_localization", how to call the recoverlocalization() API to have the robot re-position to the correct localization on the map. Before using this feature, please note the following:

- 1.The success rate of relocalization is related to the environment. Before re-positioning, it is recommended to use a clear environmental map with a sharp outline.
- 2.For the case where there is a similar environment in the map area, for example, there are offices 1 and 2 with the same environment layout on the map, if the robot is actually in the office 1, it may relocate to the office 2 during the relocalization process. . In this case, it is recommended to modify the office environment to make a distinction on the map when building the map (moving tables and chairs, adding pots, etc.).

[KBSW180140 Win32- Virtual Wall/Virtual Track Operation\(Add, Delete, Modify](#)

This document introduces the demo project of "artifacts_demo", explaining user operation of Virtual Wall /Virtual Track, including how to add/delete/modify artifacts.

[KBSW180141 Win-32- Save and Load Composite Map](#)

This document introduces the demo project of "composite_map_demo", including how to save and load maps of stcm format(composite map).

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