

Slamware

- 1.
- 2.
- 3.

- 1.
- 2.
- 3.

connect, configureNetwork5connect



1mm, 5%

D1M1D1M2E1M2260m x 260m

26m*2600m

Slamware

5cm

12slamware

SDKslamwareSDKslamware

pose, pose.

robot_studioSDK

11 2robot_size 3side_margin

ApolloSDKmoveto()Apollo

1.ApolloRoboStudio>> ⁶⁵⁷⁷⁶⁹⁵

- 2.

« SDK > slamware_sdk_windows.2.6.0_rtm.20180820 > workspaces > vs2010 > slamware_public_sdk > Debug

名称	修改日期	类型	大小
libeay32.dll	2017/4/28 14:27	应用程序扩展	1,157 KB
mapdemo.exe	2019/3/6 17:15	应用程序	6,183 KB
mapdemo.ilc	2019/3/6 17:15	Incremental Linker ...	26,846 KB
mapdemo.pdb	2019/3/6 17:15	Program Debug Da...	51,947 KB
mapdrawer_win32.exe	2019/3/6 17:18	应用程序	6,585 KB
mapdrawer_win32.ilc	2019/3/6 17:18	Incremental Linker ...	28,093 KB
mapdrawer_win32.pdb	2019/3/6 17:18	Program Debug Da...	60,275 KB
SampleDemo.exe	2019/3/7 10:14	应用程序	6,559 KB
SampleDemo.ilc	2019/3/7 10:14	Incremental Linker ...	29,685 KB
SampleDemo.pdb	2019/3/7 10:14	Program Debug Da...	61,891 KB
ssleay32.dll	2017/4/28 14:27	应用程序扩展	265 KB

VS2010SDP Minidllibeay32.dlldllibeay32.dll ssleay32.dll

Android UICommander

<https://github.com/SlamtecSupport/UICommander.Android>

```
bool setSystemParameter(const std::string& param, const std::string& value)
```

调整系统参数

参数

名称	类型	说明
param	const std::string&	调整的参数名
value	Const std::string &	调整的参数值

注：目前只支持调整系统速度的设置

param 只能取值为 SYSPARAM_ROBOT_SPEED

value 对应可取如下三种

1.SYSVAL_ROBOT_SPEED_HIGH (高)

2.SYSVAL_ROBOT_SPEED_MEDIUM (中)

3.SYSVAL_ROBOT_SPEED_LOW (低)

示例

```
bool bRet = platform.setSystemParameter(SYSPARAM_ROBOT_SPEED,  
SYSVAL_ROBOT_SPEED_HIGH);
```

(0.050.7)

```
bool bRet1 =sdp.setSystemParameter(SYSPARAM_ROBOT_SPEED, "0.3");
```

```
setSystemParameter(),SYSPARAM_ROBOT_ANGULAR_SPEEDSDK
```

```
getLaserScan()angle100000
```

```
xxxxyyaw
```

```
UImap dataRoboStudio
```

```
J22GNDRX2 pinWiFi resetWeb Portaladmin111resetAP
```

```
bool setMapUpdate(bool)
```

```
bool setMapLocalization(bool)
```

```
10s
```

[SA005 Instruction for Integrating SLAMWARE Solution in Tri-omni-wheeled Base](#)

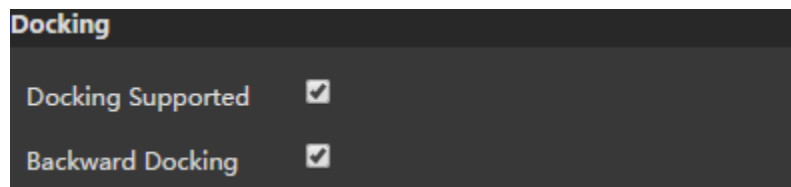
1

01

robot studiocharging/on Dock, MCU

GET_BASE_STATUSgoHomeactionstatusfinished

SlamwareDockingBackward Docking



x2 robot diameter, side margininside margin

1

0x411sRoboStudioSlamware has disconnected and reconnected againMCUs

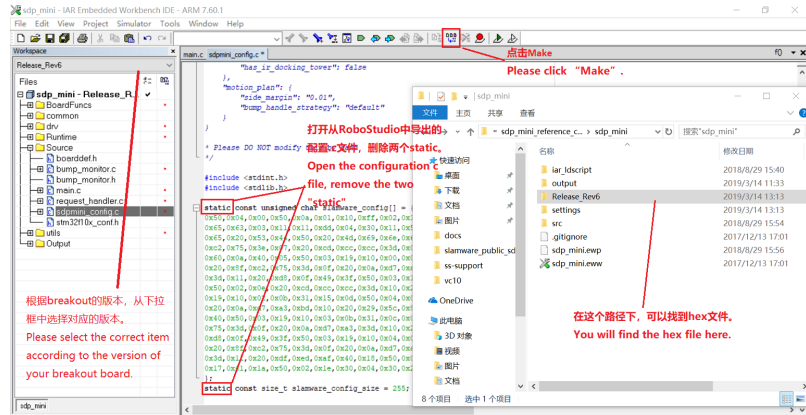
IAR 7.6IAR 7.6IAR7.6

220

slamwarewakep()Slamware>>(0,

, 32mm.

breakout 3.0 breakout 4.0 breakout 6.0



SDP Mini.csdpmi_config.cProjectProjectIAR7.6Workspacebreakout6.0Release_Rev6,.cstaticMakehexbreakoutMCU

KBSW180158 Breakout kit breakout 6.0breakout 4.0

ProjecthomeirsonarbumperControl Bushomeir

0x34GET_AUTO_HOME_DATA1

breakout

projectcontrolbusbuffer5121024

```
#define CONFIG_DRV_SERIALCHANNEL_RXBUFFERSIZE 1024
#define CONFIG_DRV_SERIALCHANNEL_TXBUFFERSIZE USART_MAX_TX_COUNT
```