

KBSW180143 SLAMWARE SDK

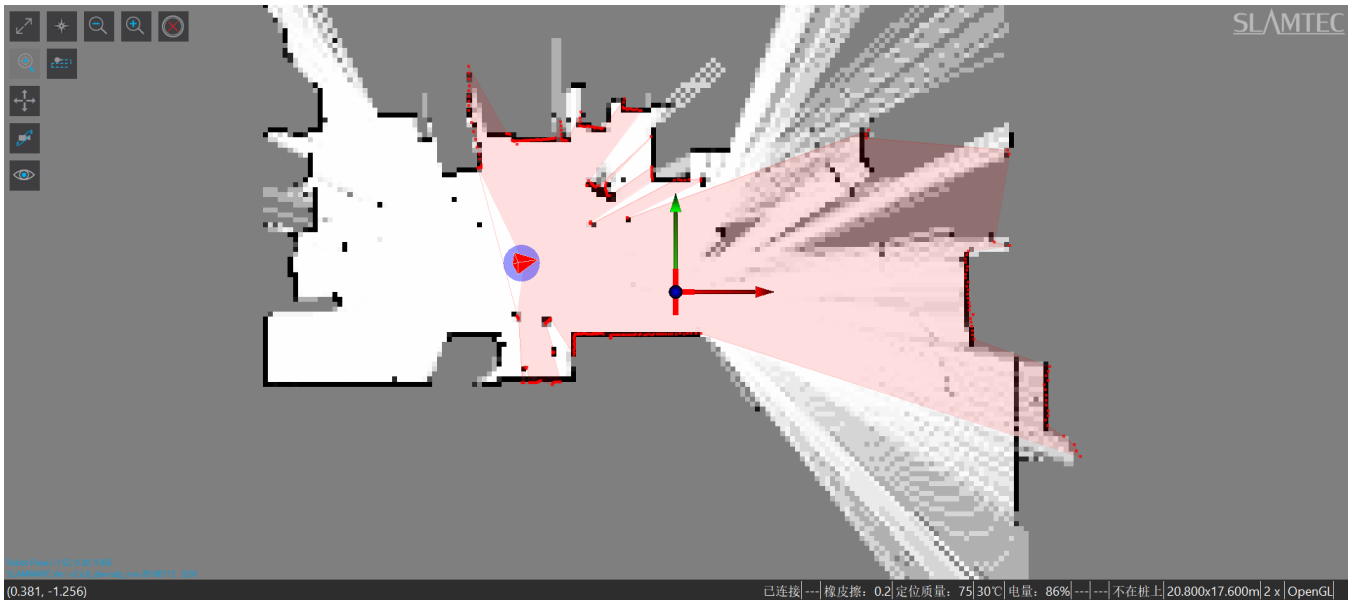
SLAMWARESDK SLAMWARESDK

Robostudio

RobostudioX Y

SLAMWARE SDP [-0.59-0.44 -157.37] [X Y yaw] X0

```
robostudio()yawgetpose()yaw(rad) = (°)*2/360
```



BMP

Slamwaremapdat bmp

Tip

windows SDKmap2bmp

Map2bmp

```
sdp = SlamwareCorePlatform::connect(opt_sdpIPAddress, opt_sdpPort);

rpos::core::RectangleF knownArea = sdp.getKnownArea(MapTypeBitmap8Bit, rpos::features::location_provider::
EXPLORERMAP); //

Map map = sdp.getMap(MapTypeBitmap8Bit, knownArea, rpos::features::location_provider::EXPLORERMAP); //

bitmap_image mapBitmap(map.getMapDimension().x(), map.getMapDimension().y()); //bmp

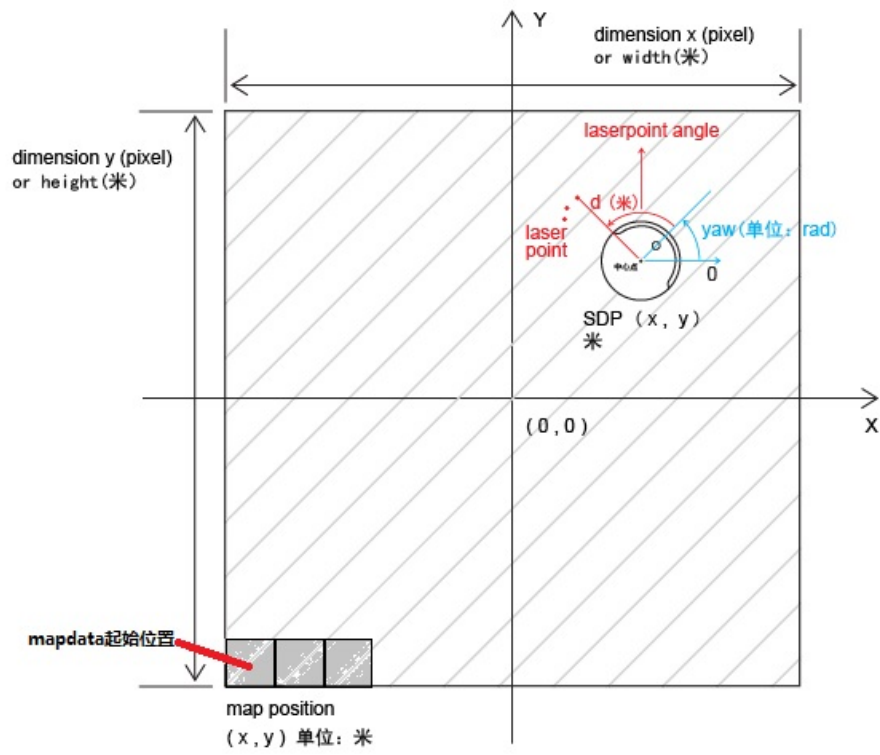
for (size_t posY = 0; posY < map.getMapDimension().y(); ++posY) //mapdatabmp
{
    for (size_t posX = 0; posX < map.getMapDimension().x(); ++posX)
    {
        rpos::system::types::_u8 cellValue = 128 + map.getMapData()[posX + (map.getMapDimension().y()-posY-1)
* map.getMapDimension().x()];
        mapBitmap.set_pixel(posX, posY, cellValue, cellValue, cellValue);
    }
}
```

getKnowArea() KnownArea, getMapDimention().x() getMapDimention().y()X, YgetMapData() -128 ~ 127 128

RoboStudiomapdata X min, Y min

Pose positionresolution.

```
, resolutiongetMapResolution()map postion, getMapPosition() SDPgetPose() yawlaser point0
```



width = resolution * dimension x
米 米/像素 像素

height = resolution * dimension y
米 米/像素 像素

known area

像素