

# 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.

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## IDE Preparation

- **Software**
  - Visual Studio 2010 SP1
  - Slamware Windows SDK:[Slamware Windows SDK](#)
  - RoboStudio(for map display):[Robostudio installer](#)
  - Sample Code:

Higher version of Visual Studio will cause errors. sometime you will need to upgrade SP1 package to make your VS compatible with .Net Framework.

- **Hardware**

Either one of following

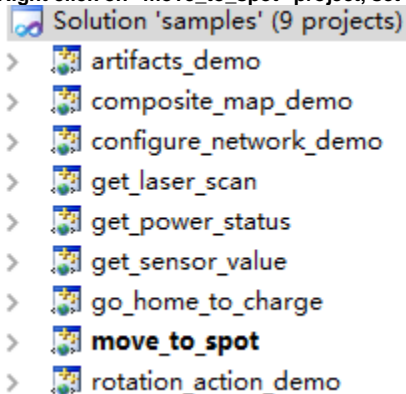
- Slamware SDP mini
- Slamware SDP
- Slamware Kit
- Zeus/Apollo robot base

## Download

[Win32-Demo](#)

## Compiling

1. Right click on "move\_to\_spot" project, set as StartUp project.



2. Right click on "move\_to\_spot", then " Properties"configure "include" and "lib" directories to the corresponding folder path of Slamware SDK.

It's not necessary to copy files to the project directory, user will only need to configure the path of SDK.



```
SlamwareCorePlatform sdp = SlamwareCorePlatform::connect(argv[1], 1445);
std::cout <<"SDK Version: " << sdp.getSDKVersion() << std::endl;
std::cout <<"SDP Version: " << sdp.getSDPVersion() << std::endl;
rpos::actions::MoveAction action = sdp.getCurrentAction();
if (action)
    action.cancel();
//move to location (2, 0), not on virtual track
rpos::features::motion_planner::MoveOptions options;
options.flag = MoveOptionFlag(MoveOptionFlagMilestone | MoveOptionFlagPrecise);
action = sdp.moveTo(rpos::core::Location(2, 0), options);
action.waitForDone();
if (action.getStatus() == rpos::core::ActionStatusError)
    std::cout << "Action Failed: " << action.getReason() << std::endl;
//draw a virtual track from (0, 0) to (2, 0), then move to (0, 0) via virtual track
rpos::core::Line line(rpos::core::Point(0,0),rpos::core::Point(2,0));
sdp.addLine(ArtifactUsageVirtualTrack, line);
options.flag = MoveOptionFlag(MoveOptionFlagKeyPoints | MoveOptionFlagPrecise);
action = sdp.moveTo(rpos::core::Location(0, 0), options);
action.waitForDone();
if (action.getStatus() == rpos::core::ActionStatusError)
    std::cout << "Action Failed: " << action.getReason() << std::endl;
```