

KBSW180121 Win32-

move_to_spot,

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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

Win32-

1. samplesmove_to_spot 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. move_to_spot, Slamware SDK includelib



Slamware SDKincludelibVisual Studio


```

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.waitUntilDone();
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.waitUntilDone();
if (action.getStatus() == rpos::core::ActionStatusError)
    std::cout << "Action Failed: " << action.getReason() << std::endl;

```