

KBSW180124 Win32-

get_sensor_value,

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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-

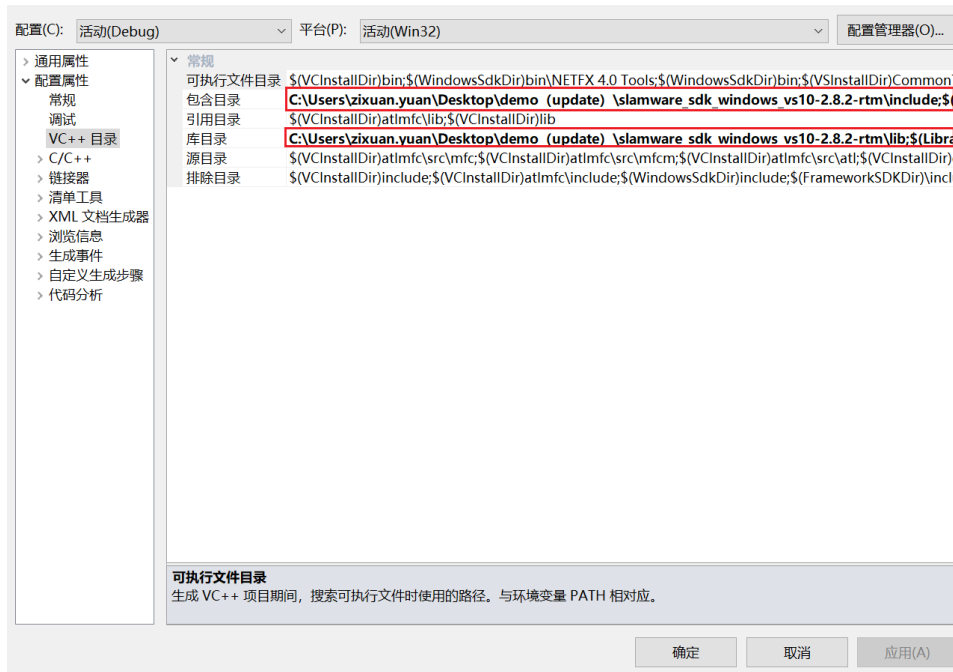
1. samplesget_sensor_value, StartUp project

- 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

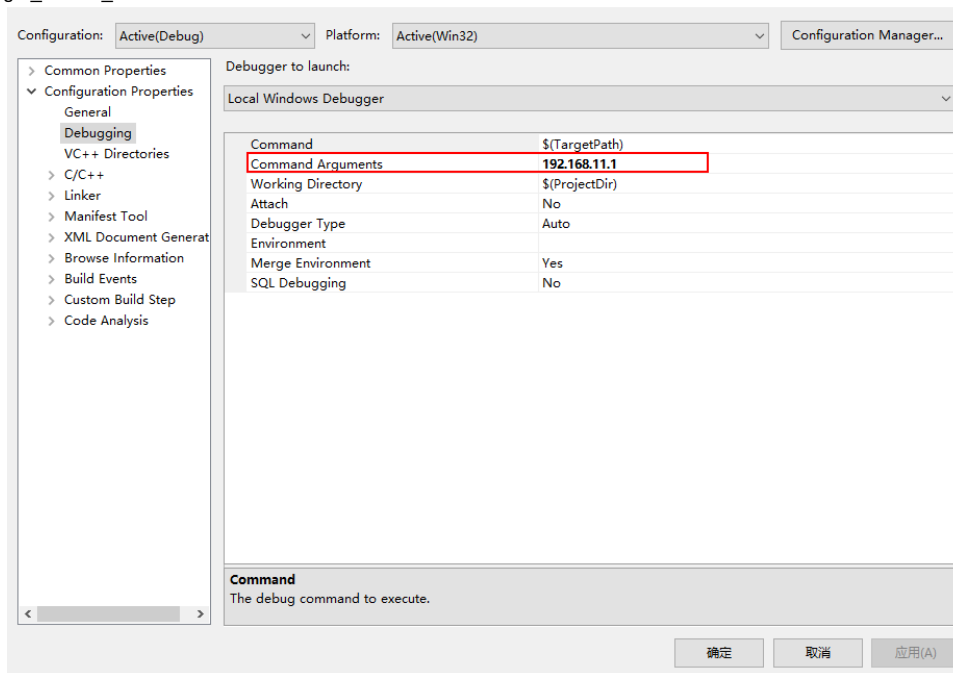
2. get_sensor_value, Slamware SDK includelib



Slamware SDKincludelibVisual Studio



3. **get_sensor_value, Debuggingcommand Arguments** 192.168.11.1
get_sensor_value <IP address>



4. F5

5. Console(sensor id 1bumper0)

```
PS C:\Users\yuan.yuan\Desktop\demo (update)\SlamwareApplicationDemos-Windows-master\Debug> .\get_sensor_value.exe 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.8.2_rtm
SDP Version: 2.8.0_rtm (Jun 16 2021)
Sensor id : 0
Sensor coreSensorType: Bumper
Sensor Type: Digital
Sensor Position: ( 0.175 , 0.126 , 0.063 ) ; Yaw = 0.624023
Sensor Value : 3.40282e+038

Sensor id : 1
Sensor coreSensorType: Bumper
Sensor Type: Digital
Sensor Position: ( 0.175 , -0.126 , 0.063 ) ; Yaw = 5.65916
Sensor Value : 0

Sensor id : 5
Sensor coreSensorType: Cliff
Sensor Type: Digital
Sensor Position: ( 0.185 , 0 , 0.038 ) ; Yaw = 0
Sensor Value : 3.40282e+038

Sensor id : 6
Sensor coreSensorType: MagTapeDetector
Sensor Type: Digital
Sensor Position: ( 0.14588 , 0.1089 , 0.03185 ) ; Yaw = 0.64126
Sensor Value : 3.40282e+038

Sensor id : 7
Sensor coreSensorType: MagTapeDetector
Sensor Type: Digital
Sensor Position: ( 0.14588 , -0.1089 , 0.03185 ) ; Yaw = 5.64193
Sensor Value : 3.40282e+038

Sensor id : 2
Sensor coreSensorType: Sonar
Sensor Type: Analog
Sensor Position: ( 0 , 0.181 , 0.1696 ) ; Yaw = 1.5708
Sensor Value : 0.196

Sensor id : 3
Sensor coreSensorType: Sonar
Sensor Type: Analog
Sensor Position: ( 0.1935 , 0 , 0.1485 ) ; Yaw = 0
Sensor Value : 0.4735
```

```
SlamwareCorePlatform sdp = SlamwareCorePlatform::connect(ip_address, 1445);
std::cout <<"SDK Version: " << sdp.getSDKVersion() << std::endl;
std::cout <<"SDP Version: " << sdp.getSDPVersion() << std::endl;
std::vector<ImpactSensorInfo> sensors;
bool result = sdp.getSensors(sensors);

if (result)
{
    for (std::vector<ImpactSensorInfo>::iterator it = sensors.begin();it != sensors.end(); ++it)
    {
        std::cout << "Sensor id : " << it->id << std::endl;
        if (it->coreSensorType == SensorTypeBumper)
            std::cout << "Sensor coreSensorType: Bumper" << std::endl;
        else if (it->coreSensorType == SensorTypeCliff)
            std::cout << "Sensor coreSensorType: Cliff" << std::endl;
        else if (it->coreSensorType == SensorTypeSonar)
            std::cout << "Sensor coreSensorType: Sonar" << std::endl;
        else if (it->coreSensorType == SensorTypeMagTapeDetector)
            std::cout << "Sensor coreSensorType: MagTapeDetector" << std::endl;
        else
            return 1;

        if (it->type == ImpactSensorTypeAnalog)
            std::cout << "Sensor Type: Analog" << std::endl;
        else if (it->type == ImpactSensorTypeDigital)
            std::cout << "Sensor Type: Digital" << std::endl;
        else
            return 1;

        std::cout << "Sensor Position: ( " << it->pose.x() << " , " << it->pose.y() << " , " << it->pose.z() << " ) ; Yaw = " << it->pose.yaw() << std::endl;

        ImpactSensorValue value;
        sdp.getSensorValue(it->id, value);
        std::cout << "Sensor Value : " << value.value<< std::endl;
    }
}
```

```
        std::cout<<std::endl;  
    }  
}
```