

# KBSW180122 Win32-/

rotation\_action\_demo,

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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

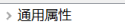
- - Slamware SDP mini
  - Slamware Slamware
  - Apollo/Ares/Athena

Win32-

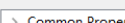
## 1. samplesrotation\_action\_demo, StartUp project

- 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. rotation\_action\_demo, Slamware SDK includelib



3. `rotation_action_demo, Debuggingco`  
`rotation_action_demo <IP address>`



4. **F5**
5. **Robostudio**

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- yawpi

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```
        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();
        //anticlockwise rotation
        rpos::core::Rotation rotation(pi*2, 0, 0);
        action = sdp.rotate(rotation);
        action.waitUntilDone();
        std::cout << "Action Status: " << action.getStatus() << std::endl;
        //clockwise rotation
rotation.yaw() = pi * (-2);
        action = sdp.rotate(rotation);
        action.waitUntilDone();
        std::cout << "Action Status: " << action.getStatus() << std::endl;
        //rotate to a certain orientation
        rpos::core::Rotation orientation(pi, 0, 0);
        action = sdp.rotateTo(orientation);
        action.waitUntilDone();
        std::cout << "Action Status: " << action.getStatus() << std::endl;
```