

KBSW183301 win32-

virtual_track_with_oa, 1. 2.

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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

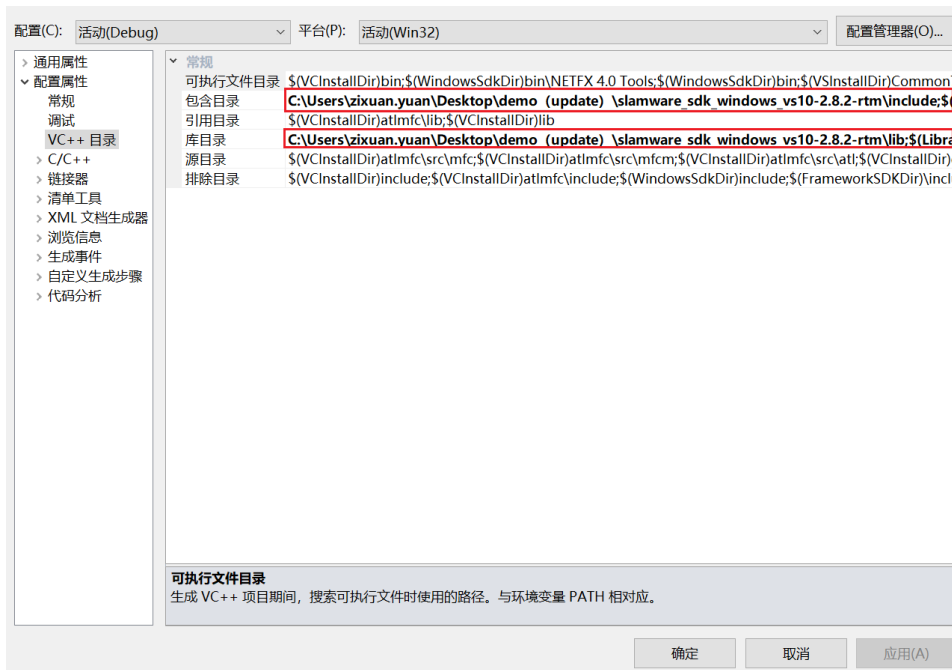
- - Slamware SDP mini
 - Slamware Slamware
 - Apollo/Ares/Athena
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Win32-

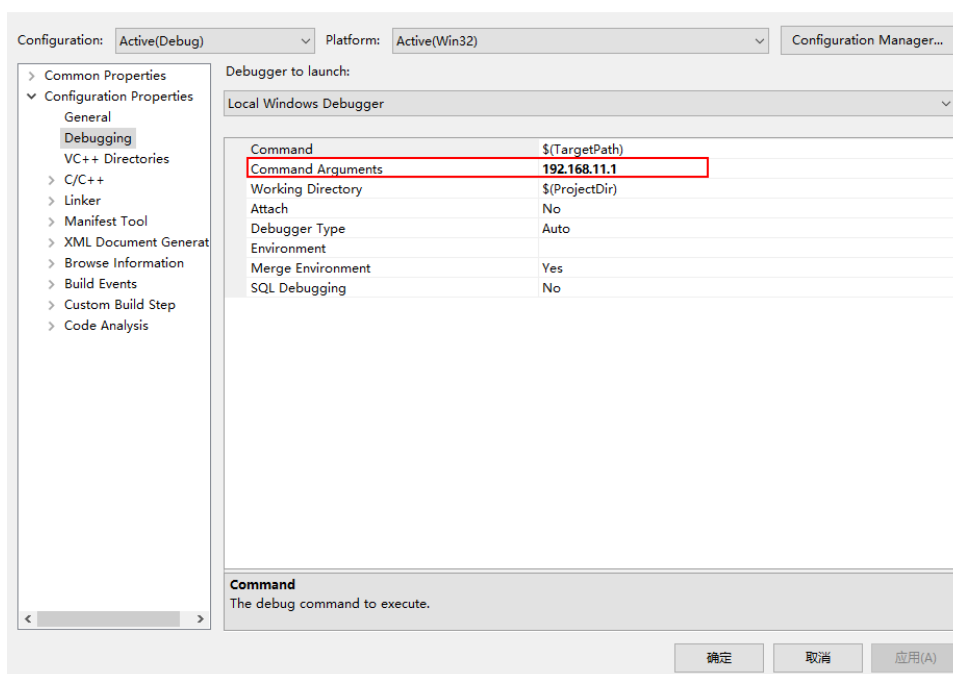
1. `samplesvirtual_track_with_oa` StartUp project
2. `virtual_track_with_oa`, Slamware SDK includelib

- i** Solution 'samples' (11 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
 - > robot_health
 - > rotation_action_demo
 - > **virtual_track_with_oa**

Slamware SDKincludelibVisual Studio



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



4. **F5**
5. **Robostudio**
Your browser does not support the HTML5 video element

- x6

```

SlamwareCorePlatform sdp = SlamwareCorePlatform::connect(ip_address, 1445);
std::cout <<"SDK Version: " << sdp.getSDKVersion() << std::endl;
std::cout <<"SDP Version: " << sdp.getSDPVersion() << std::endl;

//draw a 6 meter virtual track
rpos::core::Pose sdp_pos = sdp.getPose();
rpos::core::Line line(rpos::core::Point(sdp_pos.x(), sdp_pos.y()),rpos::core::Point
(sdp_pos.x() + 6, sdp_pos.y()));
sdp.addLine(ArtifactUsageVirtualTrack, line);

rpos::actions::MoveAction action = sdp.getCurrentAction();
if (action)
    action.cancel();

rpos::features::motion_planner::MoveOptions options;
options.flag = MoveOptionFlag
(MoveOptionFlagKeyPointsWithOA|MoveOptionFlagKeyPoints|MoveOptionFlagMilestone);
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;;

```