


# KBSW191125 Linux-x86\_64GCC4.8-

Slamware Linux SDK,

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- - Linux gcc4.9 g++4.9
  - RoboStudio(WindowsPC):[Robostudio installer](#)
  - Sample Code:

 gcc4.9g++4.9.

- - Slamware SDP mini
  - Slamware SDP
  - Slamware Slamware
  - Zeus/Apollo

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[Linux-x86\\_64\(GCC4.8\)-](#)

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1., Downloads

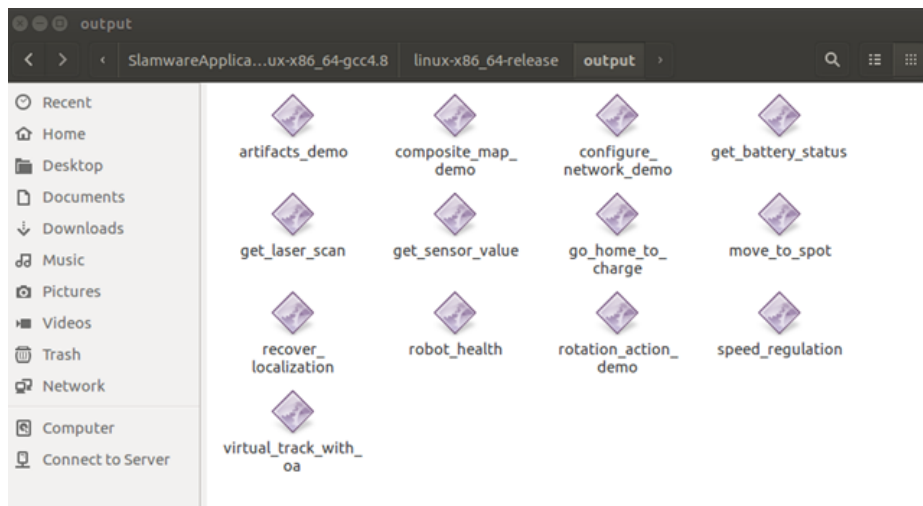
2.

- **linux-x86\_64-debug**: lib
- **linux-x86\_64-release**
- **samples**:
- compiler\_version.txt, mak\_common.inc, mak\_def.inc

3. sample, makemakefile

yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos\_Linux-x86\_64-gcc4.8/samples\$ **make**

4. make~/Desktop/SlamwareApplicationDemos\_Linux-x86\_64-gcc4.8/linux-x86\_64-release/output/



5. IP(192.168.11.1)

```
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/linux-x86_64-release/output$ ./moveandpathdemo
192.168.11.1
```

samplec++APIKBSW180105 SLAMWARE SDK API (Windows)makefile(Windows SDK sample overview(cn))

1.artifacts\_demo/

```
yzx@yzx-Baytrail-Series: ~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/linux-x86_64-release/output$ ./artifacts_demo 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.6.7_rtm
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715
Clearing existing tracks and walls...
Adding virtual walls...
Adding virtual tracks...
Moving virtual walls...
Get all tracks...
ID: 0
Start from (-1 , -1) to (-1 , 1 )
ID: 1
Start from (-1 , 1) to (1 , 1 )
ID: 2
Start from (1 , 1) to (1 , -1 )
ID: 3
Start from (1 , -1) to (-1 , -1 )
Delete track by ID, please enter track ID:
0
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/linux-x86_64-release/output$
```

2.composite\_map\_demo.stcmcomposite map



```

yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l
inux-x86_64-release/output$ ./get_battery_status 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.6.7_rtm
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715
Battery Percentage: 82
is Charging: 0
is DC connected: 0
Docking status: Not on dock

```

5.get\_laser\_scan

```

yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l
inux-x86_64-release/output$ ./get_laser_scan 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.6.7_rtm
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715
Angle: 3.13549; Distance: 0.246695; is Valid: 1
Angle: 3.10985; Distance: 0.246464; is Valid: 1
Angle: 3.06976; Distance: 0.246528; is Valid: 1
Angle: 3.06707; Distance: 0.244555; is Valid: 1
Angle: 3.05385; Distance: 0.249312; is Valid: 1
Angle: 3.04649; Distance: 0.246041; is Valid: 1

```

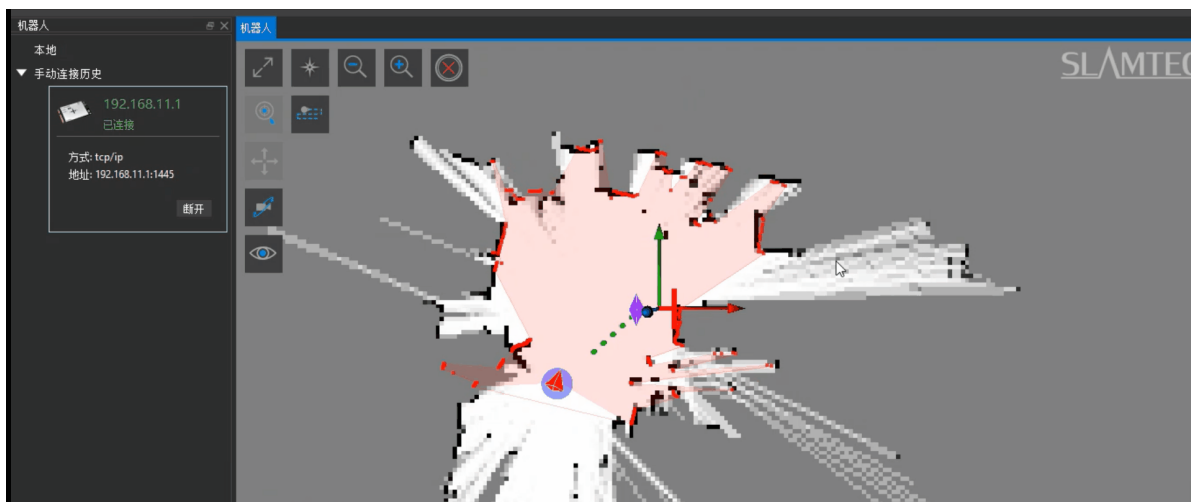
6.get\_sensor\_value

```

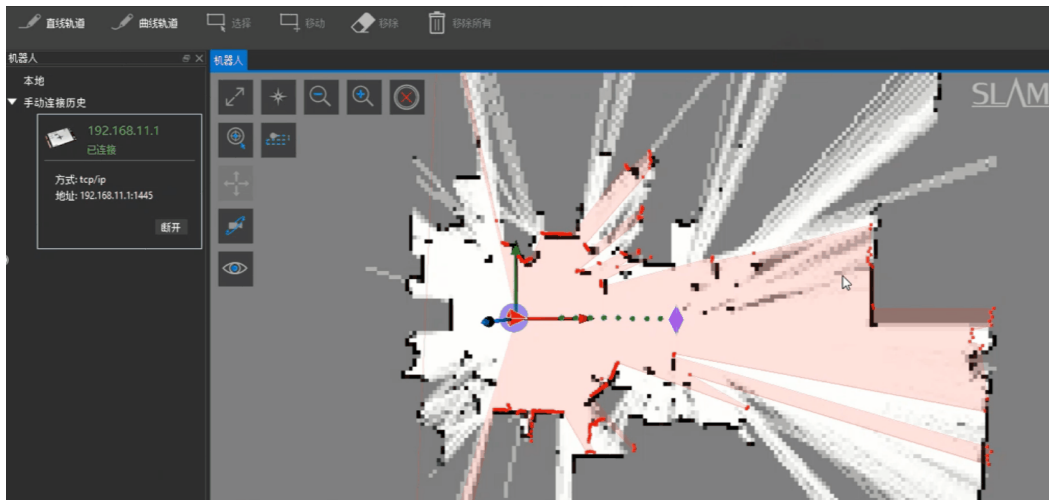
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l
inux-x86_64-release/output$ ./get_sensor_value 192.168.11.1
Connecting SDP @ 192.168.11.1...
SDK Version: 2.6.7_rtm
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715
Sensor id : 0
Sensor Kind: Sonar
Sensor Type: Analog
Sensor Position: ( 0.06 , 0.08 , 0.07 ) ; Yaw = 0.785398
Sensor Value : 4.57033e-41
Sensor id : 1
Sensor Kind: Sonar
Sensor Type: Analog
Sensor Position: ( 0.1 , 0 , 0.07 ) ; Yaw = 0
Sensor Value : 4.57033e-41
Sensor id : 2
Sensor Kind: Sonar
Sensor Type: Analog
Sensor Position: ( 0.06 , -0.08 , 0.07 ) ; Yaw = 5.49779
Sensor Value : 4.57033e-41
Sensor id : 3
Sensor Kind: Bumper
Sensor Type: Digital
Sensor Position: ( 0.06 , 0.08 , 0.07 ) ; Yaw = 0.785398
Sensor Value : 3.40282e+38
Sensor id : 4
Sensor Kind: Bumper
Sensor Type: Digital
Sensor Position: ( 0.06 , -0.08 , 0.07 ) ; Yaw = 5.49779
Sensor Value : 3.40282e+38

```

7.go\_home\_to\_chargegoHome()

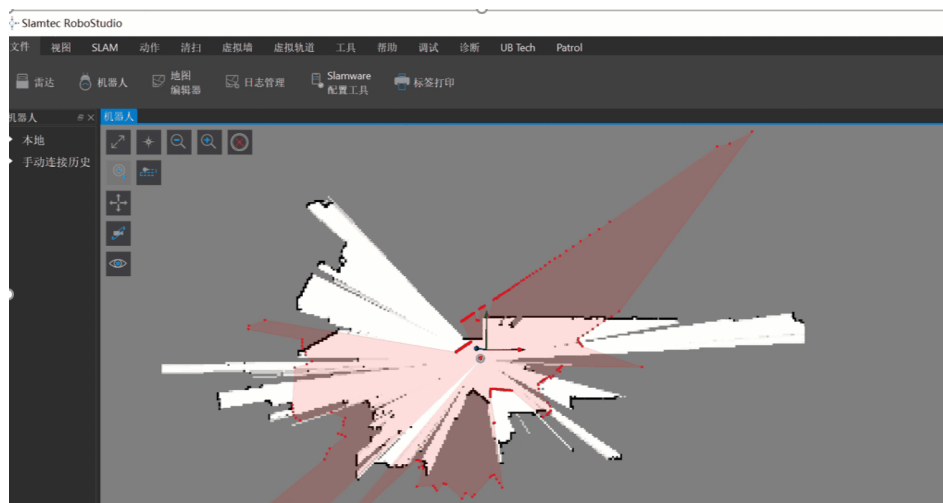


8.move\_to\_spot(2, 0) 20 0, 0



9.recover\_localizationrobostudio

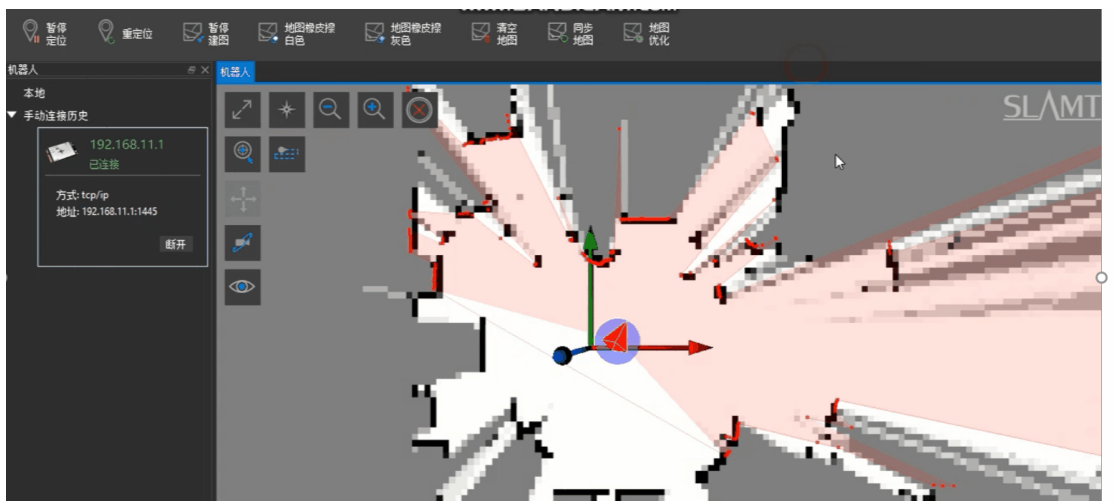
```
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l  
inux-x86_64-release/output$ ./recover_localization 192.168.11.1  
Connecting SDP @ 192.168.11.1...  
SDK Version: 2.6.7_rtm  
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715  
Current status: Running  
Current status: Running  
Current status: Running  
Current status: Running
```



10.robot\_health

```
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l  
inux-x86_64-release/output$ ./robot_health 192.168.11.1  
Connecting SDP @ 192.168.11.1...  
SDK Version: 2.6.7_rtm  
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715  
LidarDisconnected  
LidarDisconnected  
LidarDisconnected  
LidarDisconnected  
LidarDisconnected  
LidarDisconnected
```

### 11.rotation\_action\_demo yawpi



### 12.speed\_regulation

```
yzx@yzx-Baytrail-Series:~/Desktop/SlamwareApplicationDemos_Linux-x86_64-gcc4.8/l  
inux-x86_64-release/output$ ./speed_regulation 192.168.11.1  
Connecting SDP @ 192.168.11.1...  
SDK Version: 2.6.7_rtm  
SDP Version: 2.6.7_rtm-sdp-D1M1-20190715  
Robot is moving to: (1 , 0) on speed HIGH  
Robot is moving to: (-1 , 0) on speed LOW  
Robot is moving to: (0 , 1.414) on speed MEDIUM
```

### 13.virtual\_track\_with\_oax6

