

Slamware

1.
2.
3.
1.
2.
3.
- connect, configureNetwork5connect



1mm, 5%
D1M1D1M2E1M2260m x 260m
26m*2600m
Slamware

5cm
12slamware
SDKslamwareSDKslamware
pose, pose.

robot_studioSDK
11 2robot_size 3side_margin
ApolloSDKmoveto()Apollo

1.ApolloRoboStudio>>"

2.

« SDK > slamware_sdk_windows.2.6.0_rtm.20180820 > workspaces > vs2010 > slamware_public_sdk > Debug			
名称	修改日期	类型	大小
libeay32.dll	2017/4/28 14:27	应用程序扩展	1,157 KB
mapdemo.exe	2019/3/6 17:15	应用程序	6,183 KB
mapdemo.ilnk	2019/3/6 17:15	Incremental Linker ...	26,846 KB
mapdemo.pdb	2019/3/6 17:15	Program Debug Da...	51,947 KB
mapdrawer_win32.exe	2019/3/6 17:18	应用程序	6,585 KB
mapdrawer_win32.ilnk	2019/3/6 17:18	Incremental Linker ...	28,093 KB
mapdrawer_win32.pdb	2019/3/6 17:18	Program Debug Da...	60,275 KB
SampleDemo.exe	2019/3/7 10:14	应用程序	6,559 KB
SampleDemo.ilnk	2019/3/7 10:14	Incremental Linker ...	29,685 KB
SampleDemo.pdb	2019/3/7 10:14	Program Debug Da...	61,891 KB
ssleay32.dll	2017/4/28 14:27	应用程序扩展	265 KB

VS2010SDP Minidlllibeay32.dlllibeay32.dll ssleay32.dll
Android UICommander

<https://github.com/SlamtecSupport/UICommander.Android>

```
bool setSystemParameter(const std::string& param, const std::string& value)
```

调整系统参数

参数

名称	类型	说明
param	const std::string&	调整的参数名
value	Const std::string &	调整的参数值

注：目前只支持调整系统速度的设置

param 只能取值为 SYSPARAM_ROBOT_SPEED

value 对应可取如下三种

- 1.SYSVAL_ROBOT_SPEED_HIGH (高)
- 2.SYSVAL_ROBOT_SPEED_MEDIUM (中)
- 3.SYSVAL_ROBOT_SPEED_LOW (低)

示例

```
bool bRet = platform.setSystemParameter(SYSPARAM_ROBOT_SPEED, SYSVAL_ROBOT_SPEED_HIGH);
```

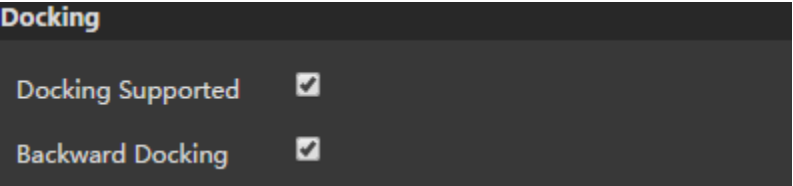
(0.050.7)

```
bool bRet1 =sdp.setSystemParameter(SYSPARAM_ROBOT_SPEED, "0.3");
setSystemParameter(),SYSPARAM_ROBOT_ANGULAR_SPEEDSDK
getLaserScan()angle100000
xxxxyyaw
UImap dataRoboStudio
J22GNDRX2 pinWiFi resetWeb Portaladmin111resetAP
bool setMapUpdate(bool)

bool setMapLocalization(bool)
10s
```

SA005 Instruction for Integrating SLAMWARE Solution in Tri-omini-wheeled Base

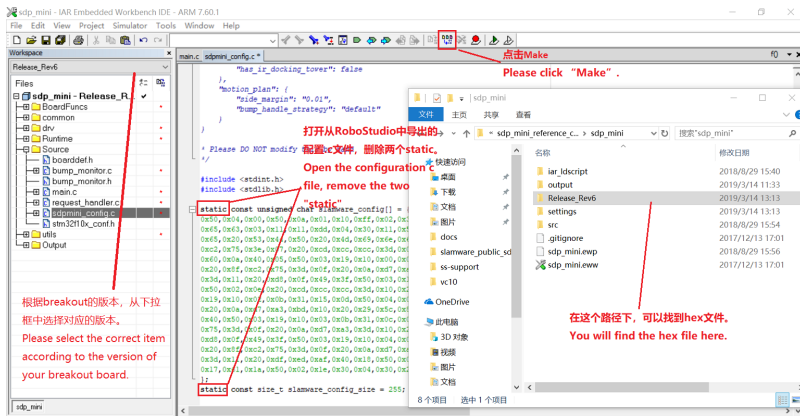
```
1
01
robot studiocharging/on Dock, MCU
GET_BASE_STATUSSgoHomeactionstatusfinished
SlamwareDockingBackward Docking
```



x2 robot diameter, side margininside margin

```
1
0x411sRoboStudioSlamware has disconnected and reconnected againMCUs
IAR 7.6IAR 7.6IAR7.6
```

```
220
slamwarewakeup()Slamware>>(0,
, 32mm.
breakout 3.0 breakout 4.0 breakout 6.0
```



SDP Mini.csdpmini_config.cProjectProjectIAR7.6Workspacebreakout6.0Release_Rev6,.cstaticMakehexbreakoutMCU
 KBSW180158 Breakout kit breakout 6.0breakout 4.0
 ProjecthomeirsonarbumperControl Bushomeir
 0x34GET_AUTO_HOME_DATA1
 breakout
 projectcontrolbusbuffer5121024

```
#define CONFIG_DRV_SERIALCHANNEL_RXBUFFERSIZE 1024
#define CONFIG_DRV_SERIALCHANNEL_TXBUFFERSIZE USART_MAX_TX_COUNT
```