Slamware

1.

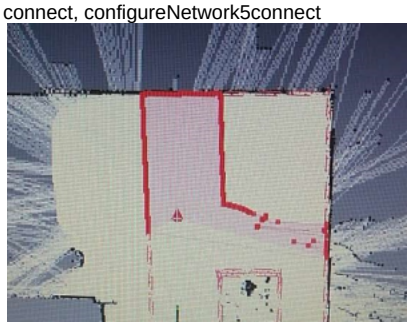
2.

3.

1.

2.

3.
connect, configureNetwork5connect



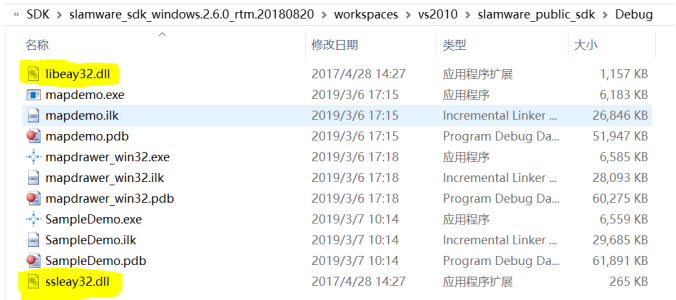
1mm, 5%
D1M1D1M2E1M2260m x 260m
26m*2600m
Slamware

5cm
12slamware
SDKslamwareSDKslamware
pose, pose.

robot_studioSDK
11 2robot_size 3side_margin
ApolloSDKmoveto()Apollo

1.ApolloRoboStudio>>“”“”

2.



VS2010SDP Minidlllibeay32.dlldlllibeay32.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

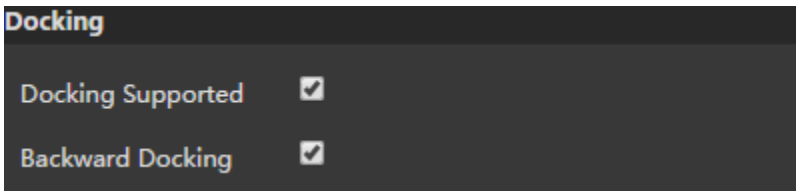
```
Bool bRet = platform.setSystemParameter(SYSPARAM_ROBOT_SPEED,
SYSVAL_ROBOT_SPEED_HIGH);
```

(0.050.7)

bool bRet1 =sdp.setSystemParameter(SYSPARAM_ROBOT_SPEED, "0.3");
setSystemParameter(),SYSPARAM_ROBOT_ANGULAR_SPEEDSDK
getLaserScan()angle100000
xxxyyaw
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_STATUSgoHomeactionstatusfinished
SlamwareDockingBackward Docking

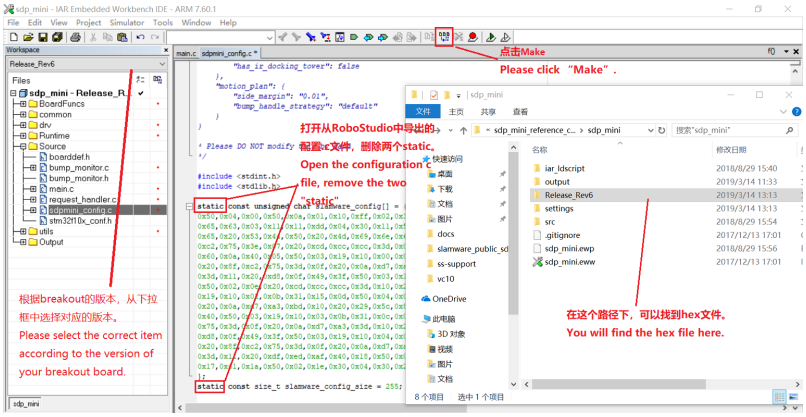


x2 robot diameter, side marginside margin

1
0x411sRoboStudioSlamware has disconnected and reconnected againMCUms
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
```