

KBSW183302 Win32-

robot_health,

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- - Visual Studio 2010 SP1
 - Slamware Windows SDK:[Slamware Windows SDK](#)
 - RoboStudio():[Robostudio installer](#)
 - Sample Code:

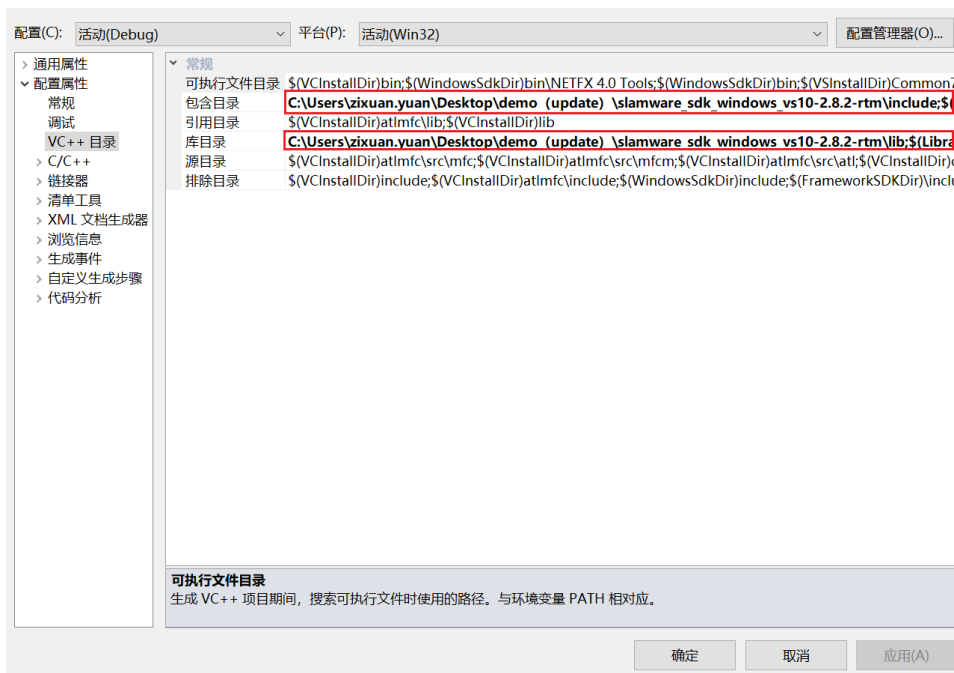
 Visual Studio
Visual Studio 2010SP1.Net FrameworkSP1

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

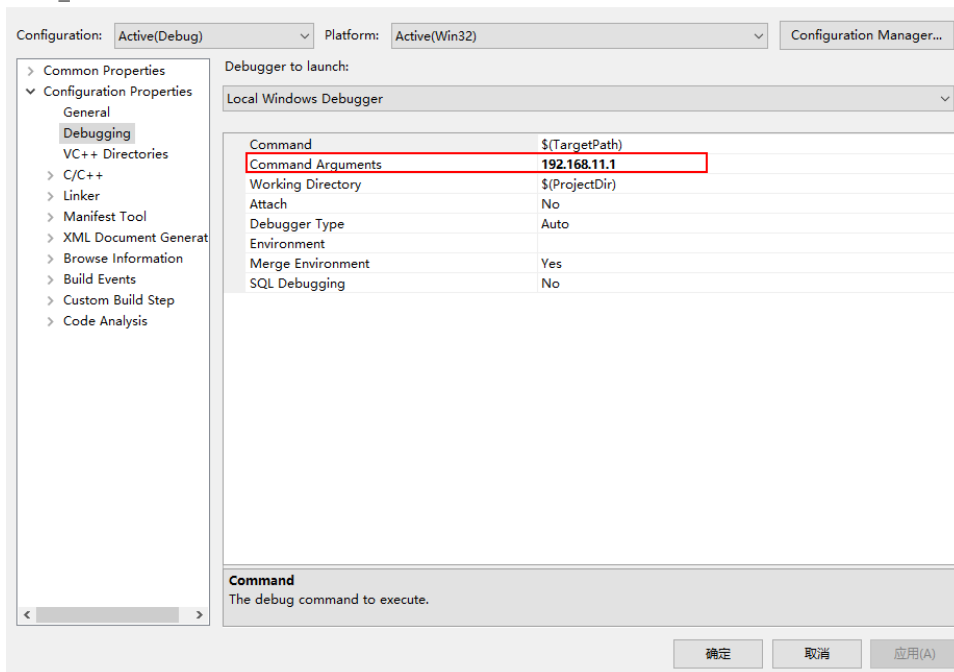
Win32-

1. **samplesrobot_health StartUp project**
 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
2. **robot_health, Slamware SDK includelib**

 Slamware SDKincludelibVisual Studio

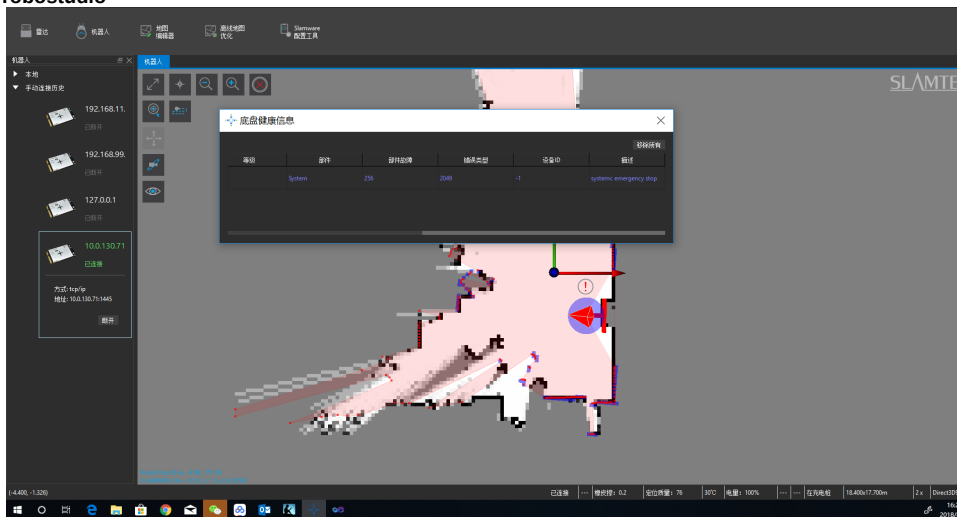


3. robot_health, Debuggingcommand Arguments 192.168.11.1 robot_health <IP address>

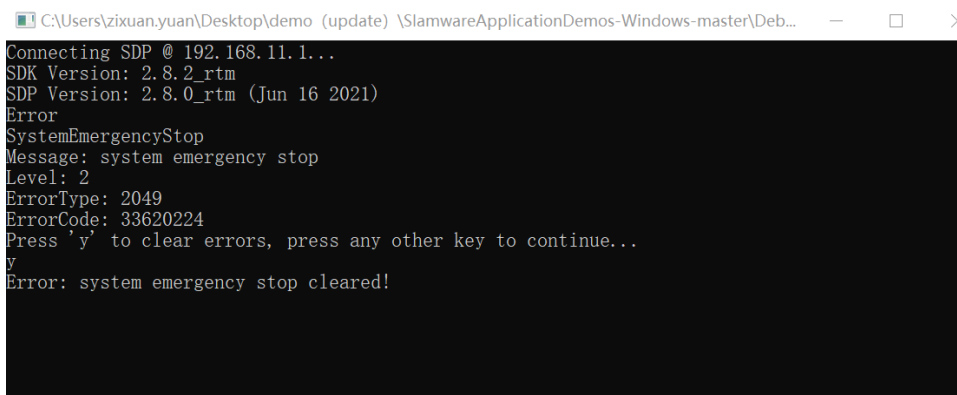


4. F5

5. robostudio



6. console



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

while(true){
    BaseHealthInfo robot_health = sdp.getRobotHealth();
    if(robot_health.hasError)
        std::cout << "Error" << std::endl;
    if(robot_health.hasFatal)
        std::cout << "Fatal" << std::endl;
    if(robot_health.hasWarning)
        std::cout << "Warning" << std::endl;
    if(*robot_health.hasLidarDisconnected)
        std::cout << "LidarDisconnected" << std::endl;
    if(*robot_health.hasSdpDisconnected)
        std::cout << "SdpDisconnected" << std::endl;
    if(*robot_health.hasSystemEmergencyStop)
        std::cout << "SystemEmergencyStop" << std::endl;
    for (auto it = robot_health.errors.begin(); it != robot_health.errors.end();
++ it) {

        std::cout << "Message: " << it->message << std::endl;
        std::cout << "Level: " << it->level << std::endl;
        std::cout << "ErrorType: "<< it->componentErrorType <<std::endl;
        std::cout << "ErrorCode: " << it->errorCode << std::endl;
```

```

    }

    int errors_size = robot_health.errors.size();
    if(errors_size > 0){
        std::cout << "Press 'y' to clear errors, press any other key to
continue..." << std::endl;

        char is_error_clear;
        std::cin >> is_error_clear;
        if(is_error_clear == 'y' || is_error_clear == 'Y') {
            for (auto it = robot_health.errors.begin(); it != robot_health.
errors.end(); ++ it) {

                sdp.clearRobotHealth(it->errorCode);
                std::cout << "Error: " << it->message << " cleared!"
<< std::endl;

            }
        }
    }
}

```