

xCore Android SDK v3.0.3更新说明

一、更新功能说明

- 修改运动指令MoveSPCommand; 增加目标点位位姿

二、MoveSPCommand使用说明

MoveSPCommand参数说明:

- 1、radius 初始半径;
- 2、rStep 半径增长率
- 3、angle 旋转角度
- 4、dir 旋转方向, true: 顺时针, false:逆时针
- 5、speed 速度
- 6、CartesianPosition: 目标点位

```
commands = new MoveAbsJCommand[]{  
    new MoveAbsJCommand(new double[]{0, Math.PI / 6, -Math.PI / 2, 0, -  
Math.PI / 3, 0}, 500, 0),  
};  
robot.moveAppend(commands);  
  
commands = new MoveLCommand[]{  
    new MoveLCommand(new double[]{0.464449, 0.136000, 0.484029, Math.PI,  
0.0, Math.PI}, 500, 50),  
};  
robot.moveAppend(commands);  
  
CartesianPosition position = new CartesianPosition(new double[]{0.464449,  
-0.136000, 0.364949, -Math.PI, Math.PI/6, -Math.PI});  
commands = new MoveSPCommand[]{  
    new MoveSPCommand(position, 0.03, 0.001, Math.PI * 6, true, 500)  
};  
robot.moveAppend(commands);
```

MoveSPCommand使用时, 需要衔接上一个轨迹; MoveSP是根据上一个轨迹的终点为起点开始运动; 因此, MoveSPCommand需要和一段运动轨迹合并使用;