3. Set the type of bottom plate car

3.1 Statement

Since the ROS driver board is adapted to several car types, the factory default is not the sunriseRobot car type, so it needs to be set to sunriseRobot type to be used, otherwise there will be abnormal control problems.

The type ID of sunriseRobot = 6 can be seen from the driver library.

```
self.CARTYPE_X3 = 0x01
self.CARTYPE_X3_PLUS = 0x02
self.CARTYPE_X1 = 0x04
self.CARTYPE_R2 = 0x05
self.CARTYPE_SUNRISE = 0x06
```

If the factory image of RDK X3 robot car is used, the self-starting APP will automatically set the car type to sunriseRobot type. Therefore, after starting the APP control program with the factory image, the car type will automatically be set to the RDK X3 robot car type. Running the ROS routine also automatically sets the car type to the RDK X3 robot car type.

Please refer to the following routine to manually set the car type:

3.2. Set and read the car type

Source path: / root/sunriseRobot _basic/Samples / 1/2 _set_cartype. Ipynb

Open jupyterlab, find and run the program to see the results.

Set the car type to 6. After receiving this command, the ROS expansion board will save this parameter and remember this parameter the next time you start up.

```
# 设置小车类型为sunriseRobot
# Set the car type to sunriseRobot
bot.set_car_type(6)
```

Read the car type, read out the type value =6, the setting is complete.

```
car_type = bot.get_car_type_from_machine()
print(car_type)
```