# Set robot car type and lidar model

Note: Since the ROSMASTER series robots are divided into multiple types of robots and multiple types of equipment, the factory system has been configured with routines for multiple types of equipment.

However, since the product cannot be automatically identified, the machine type and radar model need to be manually set.

There are two ways to set the machine type. The first is to modify it by running a script program, and the second is to use the mobile APP to connect and control the car.

The APP will automatically set the car type according to the selection. **(Method 2 is not applicable to pi5!!)**

X3 PLUS   X3   R2   R2L   X1
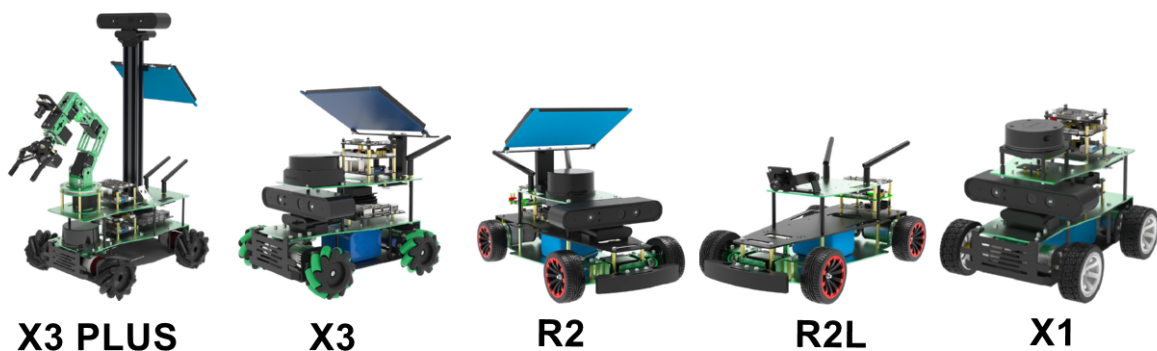
The car is set to the X3 model by default when leaving the factory. We need to set it to the R2 model. In addition, the R2 model has two lidars, namely the Silan radar a1 and the EAI radar 4ROS. When setting the model radar parameters, the same is true. Needs to be taken into account. The setting method is as follows,

1. Open the terminal and enter

```
#Raspberry Pi 5 master needs to enter docker first, please perform this step
#If running the script into docker fails, please refer to ROS/07, Docker
tutorial
~/run_docker.sh
```

```
#If it is a user input that purchased a1 radar
sh ~/Rosmaster/RobotType/set_R2_A1.sh
#If it is a user input who purchased 4ROS radar
sh ~/Rosmaster/RobotType/set_R2_4ROS.sh
```

2. To check whether it takes effect, we reopen a terminal and see if what is printed by the terminal corresponds to the car model and radar model of the product.

3. When the mobile APP connects and controls the car, it is also necessary to set the car model. For the setting method here, refer to the APP remote control tutorial. Just select the corresponding product model and operate the car to control the car. The APP will set the type according to the selected car