Set Robot car type and lidar model

Note: Since ROSMASTER series robots are have multiple types(X3/X3 PLUS/X1/R2/R2L), the system file from factory has been configured with routines for multiple types hardware configurations. But since the system cannot automatically identify the product, user needs to manually set the machine type and lidar model.

X3 PLUS   **X3**   **R2**   **R2L**   **X1**

Case1:If you want to use APP control robot

Please refer to the APP remote control course, and directly select the corresponding product model in the APP to operate the control car.

Case2: If you want to enter system to edit code

Please check following steps.

1. Open the terminal of the robot system
2. If you are using ROSMASTER X3 + A1 Lidar. You need to input following command to set robot model and lidar model.

```
sh ~/Rosmaster/RobotType/set_X3_A1.sh
```

If you are using ROSMASTER X3 + S2 Lidar. You need to input following command to set robot model and lidar model.

```
sh ~/Rosmaster/RobotType/set_X3_S2.sh
```

If you are using ROSMASTER X3 PLUS. You need to input following command to set robot model and lidar model.

```
sh ~/Rosmaster/RobotType/set_X3Plus.sh
```

3.Close the terminal, open it again, and see if the corresponding product model number is printed.

```
workspace link to X3plus + ROBOT_TYPE: X3plus
----------------------
MY_IP: 192.168.2.132
ROS_MASTER_URI:
http://192.168.2.132:11311
my_robot: X3plus | my_lidar: 4ROS
----------------------
jetson@yahboom:~$
```