先读我

1. 运行 Demo 需以下步骤

1. 电脑可用网线连接控制器的网口，然后设置固定 IP，与控制器 IP 在同一网段下。也可无线连接控制器。
    - 四轴机器人（如MG400等） 有线连接时连接LAN1：ip为192.168.1.6 , 有线连接时连接LAN2：ip为192.168.2.6
    - 六轴机器人（如CR系列等） 有线连接：ip为192.168.5.1 , 无线连接：ip为192.168.1.6
2. 尝试 ping 通控制器 IP，确保在同一网段下。

2. 文件说明

1. inc 文件夹：函数接口 DobotDll.h、使用的结构体类型 DobotTypes.h，可根据这些文件修改 DobotSDK.py。
2. 根目录：使用 Qt 5.12.6-MinGW-64 位的编译器生成的动态库以及所有依赖。
3. Demo_FourAxis.py: 示例适配四轴机器人（例：MG400等）。
4. Demo_SixAxis.py: 示例适配六轴机器人（例：CR系列等）。

3. 动态库版本说明

注意：不同版本提供的函数支持的机械臂控制器版本不同，如果控制器版本低于 SDK 版本，可能会不支持某些函数。

1. 当前版本：V1.3.0_alpha1
2. 支持的控制器版本：3.4.0 版本及以上

4. 运行Demo

方法一: 需要检测搜索到动态库，需在**VsCode**中打开PythonDemo_Windows整个目录，再直接运行 Demo_SixAxis.py 或 Demo_FourAxis.py 。
方法二: 需要检测搜索到动态库，需在**PyCharm**中打开PythonDemo_Windows整个目录，再直接运行 Demo_SixAxis.py 或 Demo_FourAxis.py 。

5. 测试环境

- language: Python 3.7 64-bit
- dll: Qt 5.12.6 MinGW 64-bit
- os: Windows 10 64-bit

Readme

1. The following steps are required to run Demo

1. The computer can be connected to the network port of the controller with a network cable, and then set a fixed IP, which is in the same network segment as the controller IP. The controller can also be connected wirelessly.
    - Four-axis robot (such as MG400, etc.) When wired connection, connect to LAN1: ip is 192.168.1.6 , When wired connection, connect to LAN2: ip is 192.168.2.6 .
    - Six-axis robot (such as CR series, etc.) Wired connection: ip is 192.168.5.1 ,Wireless connection: ip is 192.168.1.6 .
2. Try to ping the controller IP to make sure it is in the same network segment.

2. File description

1. inc folder: function interface in DobotDll.h, structure type in DobotTypes.h, you can modify DobotSDK.py according to these files.
2. root directory: dynamic library and all dependencies generated by Qt 5.12.6-MinGW-64 bit compiler.
3. Demo_FourAxis.py: The example is suitable for four-axis robots (example: MG400, etc.).
4. Demo_SixAxis.py: The example is suitable for six-axis robots (example: CR series, etc.).

3. Dynamic library version description

Note: The functions provided by different versions support different versions of the robotic arm controller. If the controller version is lower than the SDK version, some functions may not be supported.

1. Current version: V1.3.0_alpha1

2. Supported controller version: 3.4.0 version and above

4. Run Demo

Method 1: To detect and search for dynamic libraries, open the entire PythonDemo_Windows directory in **VsCode**, and then run Demo_SixAxis.py or Demo_FourAxis.py directly.
Method 2: To detect and search for dynamic libraries, open the entire PythonDemo_Windows directory in **PyCharm**, and then run Demo_SixAxis.py or Demo_FourAxis.py directly.

5. Test environment

- language: Python 3.7 64-bit
- dll: Qt 5.12.6 MinGW 64-bit
- os: Windows 10 64-bit