

## Workaround

Got an error when building pathmotion tests, this is my temporary workaround.

🔗 master

👤 kevinAlfsen committed 1 minute ago

1 parent [0973512](#) commit [144581d](#)

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38 pathmake/lib/pathmake.klc

```

488 488
489 489     END planPath
490 490
491 - ROUTINE planImportPath
492 - BEGIN
493 -     IF this.usePathPlan THEN
494 -         `PATH_PLAN_NAME`__new(this.origin)
495 -         `PATH_PLAN_NAME`__importPath(filename)
496 -
497 -         IF raster_type = NEARESTNEIGHBOR THEN
498 -             `PATH_PLAN_NAME`__NN_graph
499 -         ELSE
500 -             --(poly_depend, strict_dir)
501 -             `PATH_PLAN_NAME`__raster_graph(raster_type, poly_depend, TRUE)
502 -         ENDIF
503 -
504 -         `PATH_PLAN_NAME`__MST(`PATH_PLAN_NAME`__closest_bounding_box(start_corner))
505 -
506 -         --set point orientation
507 -         `PATH_PLAN_NAME`__set_orientation(
508 -             paths__set_orientation((this.coord_system.system), this.idod) )
509 -         ENDIF
510 -     END planImportPath
511 + --ROUTINE planImportPath
512 + -- BEGIN
513 + --     IF this.usePathPlan THEN
514 + --         `PATH_PLAN_NAME`__new(this.origin)
515 + --         `PATH_PLAN_NAME`__importPath(filename)
516 + --
517 + --         IF raster_type = NEARESTNEIGHBOR THEN
518 + --             `PATH_PLAN_NAME`__NN_graph

```

```

499 + --      ELSE
500 + --          --(poly_depend, strict_dir)
501 + --          `PATH_PLAN_NAME`__raster_graph(raster_type, poly_depend, TRUE)
502 + --      ENDIF
503 + --
504 + --          `PATH_PLAN_NAME`__MST(`PATH_PLAN_NAME`__closest_bounding_box(start_corner))
505 + --
506 + --          --set point orientation
507 + --          `PATH_PLAN_NAME`__set_orientation(
          paths__set_orientation((this.coord_system.system), this.idod) )
508 + --      ENDIF
509 + --  END planImportPath
510 510
511 511  ROUTINE get_start_node
512 512  BEGIN

```

4 pathmake/lib/pathmake.klh

```

67 67  declare_member(class_name,planPath,class_name,pthp1)
68 68  ROUTINE planPath(lines : PATH nodedata = t_VEC_PATH; contours : PATH nodedata =
        t_VEC_PATH; &
69 69          start_corner : INTEGER; raster_type : INTEGER; poly_depend : BOOLEAN)
        FROM class_name
70 - declare_member(class_name,planImportPath,class_name,ldpth)
71 - ROUTINE planImportPath(filename : STRING; start_corner : INTEGER; raster_type :
        INTEGER; poly_depend : BOOLEAN; intrep_tool : BOOLEAN) FROM class_name
70 + -- declare_member(class_name,planImportPath,class_name,ldpth)
71 + -- ROUTINE planImportPath(filename : STRING; start_corner : INTEGER; raster_type :
        INTEGER; poly_depend : BOOLEAN; intrep_tool : BOOLEAN) FROM class_name
72 72  declare_member(class_name,get_start_node,class_name,gtsrn)
73 73  ROUTINE get_start_node : XYZWPR FROM class_name
74 74  declare_member(class_name,get_end_node,class_name,gtedn)

```

10 pathmotion/test/test\_pth\_mtn.kl

```

187 187
188 188  --generate path
189 189  --(lines, contours, start_corner, raster_type, poly_depend, contourFirst)
190 - tstpth__planPath(lines, contours, PLATE_CORNER, ONEWAY, FALSE, FALSE)
190 + tstpth__planPath(lines, contours, PLATE_CORNER, ONEWAY, FALSE)
191 191
192 192  -- approach path
193 193  tstmtm__run_approach_path(LINKING_SPEED, LINKING_STEP, (cds.system), PAD_IDOD,
        origin, POS(0,100,-1*RETRACT_HEIGHT,0,0,0,(ZEROPOS(1).config_data)))
267 267  --generate path
268 268  bbox = tstcanv__get_bounding_box_drawing
269 269  --(lines, contours, start_corner, raster_type, poly_depend, contourFirst)
270 - tstpth__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE, FALSE)
270 + tstpth__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE)
271 271
272 272  -- approach path
273 273  tstmtm__run_approach_path(LINKING_SPEED, LINKING_STEP, (cds.system), PAD_IDOD,
        origin, POS(0,100,RETRACT_HEIGHT,0,0,0,(ZEROPOS(1).config_data)))

```

```

348 348
349 349 --generate path
350 350 --(lines, contours, start_corner, raster_type, poly_depend, contourFirst)
351 351 - tstpth__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE, FALSE)
351 351 + tstpth__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE)
352 352 --pause
353 353
354 354 -- approach path
429 429
430 430 --generate path
431 431 --(lines, contours, start_corner, raster_type, poly_depend, contourFirst)
432 432 - tstpth__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE, FALSE)
432 432 + tstpth__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE)
433 433 --pause
434 434
435 435 -- approach path
508 508
509 509 --generate path
510 510 --(lines, contours, start_corner, raster_type, poly_depend, contourFirst)
511 511 - tstpth__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE, FALSE)
511 511 + tstpth__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE)
512 512 --pause
513 513
514 514 -- approach path

```

10 pathmotion/test/test\_pth\_rot.kl

```

209 209
210 210 --generate path
211 211 -- (lines, contours, start_corner, raster_type, poly_depend, contourFirst)
212 212 - tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE, FALSE)
212 212 + tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE)
213 213
214 214 -- approach path
215 215 tstrmn__run_approach_path(LINKING_SPEED, LINKING_STEP, (cds.system), PAD_IDOD,
origin, POS(0,START_DIST+100,-1*RETRACT_HEIGHT,0,0,0,(ZEROPOS(1).config_data)))
310 310
311 311 --generate path
312 312 -- (lines, contours, start_corner, raster_type, poly_depend, contourFirst)
313 313 - tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE, FALSE)
313 313 + tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE)
314 314
315 315 -- approach path
316 316 tstrmn__run_approach_path(LINKING_SPEED, LINKING_STEP, (cds.system), PAD_IDOD,
origin, POS(0,PAD_START_DIST+100,-1*RETRACT_HEIGHT,0,0,0,(ZEROPOS(1).config_data)))
401 401
402 402 --generate path
403 403 -- (lines, contours, start_corner, raster_type, poly_depend, contourFirst)
404 404 - tstrot__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE, FALSE)
404 404 + tstrot__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE)
405 405
406 406 --set path type
407 407 tstrmn__set_prog_names(MOVE_DRYRUN)

```

```
510 510
511 511 --generate path
512 512 -- (lines, contours, start_corner, raster_type, poly_depend, contourFirst)
513 513 - tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE, FALSE)
514 513 + tstrot__planPath(lines, contours, OD_CORNER, ONEWAY, FALSE)
514 514
515 515 -- approach path
516 516 tstrmn__run_approach_path(LINKING_SPEED, LINKING_STEP, (cds.system), PAD_IDOD,
origin, offst)
602 602
603 603 --generate path
604 604 -- (lines, contours, start_corner, raster_type, poly_depend, contourFirst)
605 605 - tstrot__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE, FALSE)
606 605 + tstrot__planPath(lines, contours, ID_CORNER, ONEWAY, FALSE)
606 606
607 607 --set path type
608 608 tstrmn__set_prog_names(MOVE_DRYRUN)
```

0 comments on commit [144581d](#)