

switch_mode.cpp

This example demonstrates how to configure the speed profile and switch robot modes.

This example demonstrates how to configure the speed profile and switch robot modes. Before sending any motion commands, you must switch the robot to the appropriate control mode. By default, the robotic arm starts in `RobotMode::PLANNING_POS`. To use other control modes, such as servo control, you must explicitly switch to them.

This example shows how to:

- Set a predefined speed profile.
- Switch the robot to `RobotMode::SERVO_JOINT_POS` using two equivalent approaches.

Example usage:

```
#include "airbot_sdk.hpp"
using namespace airbot;

int main() {
    auto sdk = std::make_shared<AirbotSdk>("192.168.0.xxx", 50051);

    // Set predefined speed profile
    sdk->SetSpeedProfile(SpeedProfile::DEFAULT);

    // Switch control mode to SERVO_JOINT_POS
    sdk->SwitchMode({RobotMode::SERVO_JOINT_POS});

    // Alternatively, specify target group name explicitly
    sdk->SwitchMode({"arm"}, {RobotMode::SERVO_JOINT_POS});

    return 0;
}
```