KBSW183506 Android-

SpeedRegulation , setSystemParameter

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  - Android Studio 3.1.3
  - Slamware Android SDK: slamware_sdk_android.2.6.0_rtm.20180820.tar.gz
  - RoboStudio():Robostudio installer
  - Sample Code:

    > Android Studiobuild.gradleSlamware Android SDK 2.6.0 SDK slamware_sdk_android.jar librpsdk.so

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  - Slamware SDP mini
  - Slamware SDP
  - Slamware Slamware
  - Zeus/Apollo

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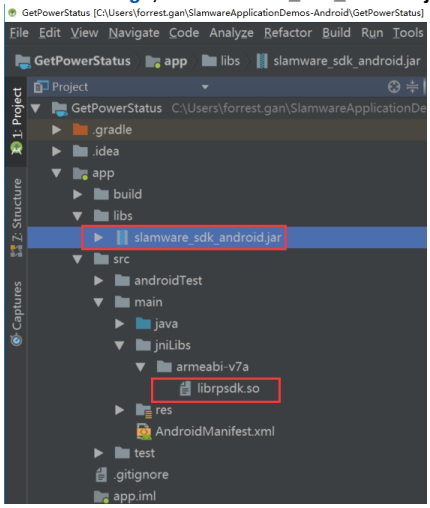
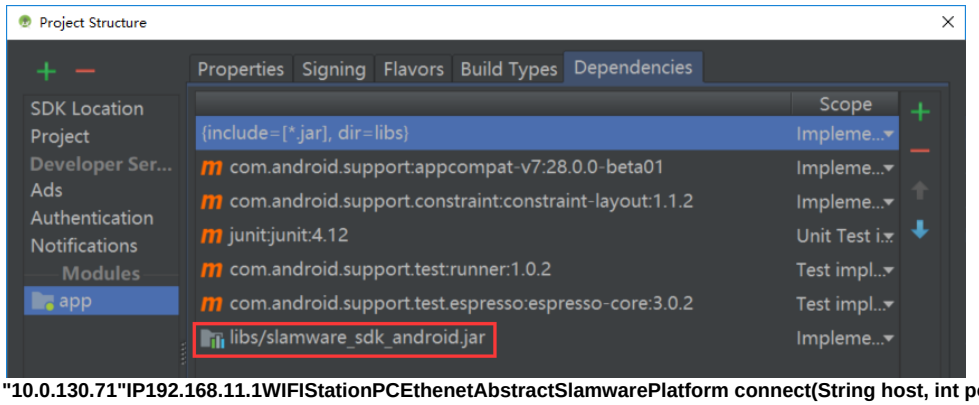
1. **GoHomeCharge,libs slamware_sdk_android.jar jinLibs librpsdk.so SDK**



2. **Project Structure --> app --> Dependencies Slamware SDK**



3. **"10.0.130.71"IP192.168.11.1WIFIStationPCEthenetAbstractSlamwarePlatform connect(String host, int port)hostIPport**

```
/*  */
AbstractSlamwarePlatform robotPlatform = DeviceManager.connect("10.0.130.71", 1445);
```

4. **AndroidWIFIshift + F10**

> SDKAndroid

5. **RoboStudio**
   Your browser does not support the HTML5 video element

- **slamcore0.15m/s 0.25m/s 0.35m/s**

```
/*  */
final AbstractSlamwarePlatform robotPlatform = DeviceManager.connect("10.0.130.71", 1445);

IMoveAction action;

try {
    action = robotPlatform.getCurrentAction();
} catch (ConnectionFailException e) {
        /* Exception Handle code*/
        ....
}

Location location1 = new Location(0, 1, 0);
Location location2 = new Location(1, 0, 0);
Location location3 = new Location(0, 0, 0);

while (true) {
try {

        action = robotPlatform.moveTo(location1, false, true);
        if (action.getStatus() == ActionStatus.ERROR) {
                Log.d(TAG, "Acvtion Faild, " + action.getReason());
        }
        robotPlatform.setSystemParameter(SYSPARAM_ROBOT_SPEED, SYSVAL_ROBOT_SPEED_HIGH);
        Log.d(TAG, "Robot is moving to " + "(" + location1.getX() + ", " + location1.getY() + ")");
        action.waitUntilDone();

        action = robotPlatform.moveTo(location2, false, true);
        if (action.getStatus() == ActionStatus.ERROR) {
                Log.d(TAG, "Acvtion Faild, " + action.getReason());
        }
        robotPlatform.setSystemParameter(SYSPARAM_ROBOT_SPEED, SYSVAL_ROBOT_SPEED_LOW);
        Log.d(TAG, "Robot is moving to " + "(" + location2.getX() + ", " + location2.getY() + ")");
        action.waitUntilDone();

        action = robotPlatform.moveTo(location3, false, true);
        if (action.getStatus() == ActionStatus.ERROR) {
                Log.d(TAG, "Acvtion Faild, " + action.getReason());
        }
        robotPlatform.setSystemParameter(SYSPARAM_ROBOT_SPEED, SYSVAL_ROBOT_SPEED_MEDIUM);
        Log.d(TAG, "Robot is moving to " + "(" + location3.getX() + ", " + location3.getY() + ")");
        action.waitUntilDone();

} catch (ConnectionTimeOutException e) {
        /* Exception Handle code*/
        ....
}
```