

KBSW180106 SLAMWARE SDK API (Android)

AndroidSLAMWARE SDKAPI

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 - IAction
 - IMoveAction IAction
 - ISweepMoveAction
 - ISweepMoveAction IAction
 - path
 - ActionStatus
 - MoveDirection
- com.slamtec.slamware.discovery
 - AbstractDiscover.BleConfigureListener
 - AbstractDiscover
 - AbstractDiscover.DiscoveryListener
 - BleDevice
 - Device
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 - SensorType
 - SlamcoreShutdownParam
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 - RestartMode
 - LineMap
 - PointsMap
 - ImpactSensorInfo
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 - ImpactSensorValue
- com.slamtec.slamware.exceptions

- AlreadyConnectedException
- ConnectionFailException
- ConnectionLostException
- ConnectionTimeOutException
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- OperationFailException
- OutOfResourceException
- ParseInvalidException
- PathFindFailException
- RequestFailException
- RequestTimeOutException
- UnauthorizedRequestException
- UnsupportedCommandException
- com.slamtec.slamware.message
 - DepthCameraFrame
- com.slamtec.slamware.sdp
 - Action
 - CompositeMapHelper

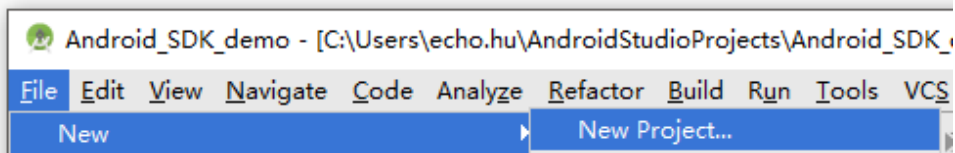
Android Slamware SDK

- Android 4.3Android 4.3

SDK

- Slamware Android SDKslamtec_agent.jararmeabiSDKAndroid

1. Android StudioFile>New>New ProjectAndroid Studio Start a new Android Studio Project



2.

The screenshot shows the 'Create New Project' dialog in Android Studio. The title bar reads 'Create New Project'. The main header area contains the Android Studio logo and the text 'New Project' and 'Android Studio'. Below this, the heading 'Configure your new project' is displayed. The form contains the following fields:

- Application name:** My Application
- Company Domain:** slamtec.com
- Package name:** com.slamtec.myapplication (with an [Edit](#) link)
- Project location:** C:\Users\echo.hu\AndroidStudioProjects\MyApplication (with a browse button)

At the bottom right, there are four buttons: 'Previous', 'Next' (highlighted in blue), 'Cancel', and 'Finish'.

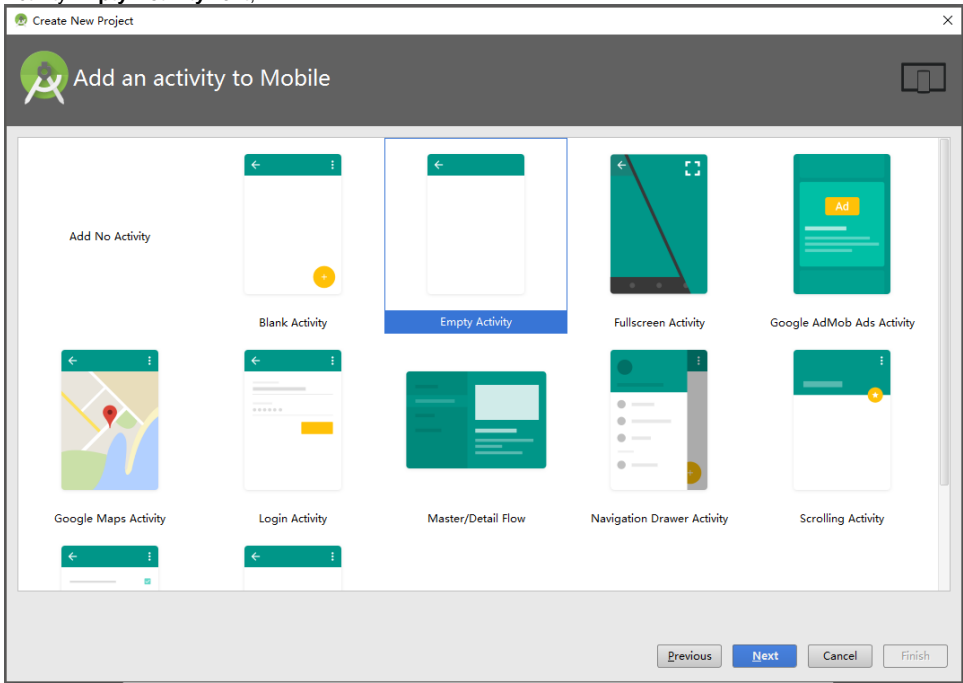
3. Next

The screenshot shows the 'Create New Project' dialog in Android Studio, specifically the 'Target Android Devices' step. The title bar reads 'Create New Project'. The main header area contains the Android Studio logo and the text 'Target Android Devices'. Below this, the heading 'Select the form factors your app will run on' is displayed, followed by the sub-heading 'Different platforms may require separate SDKs'. The form contains the following options:

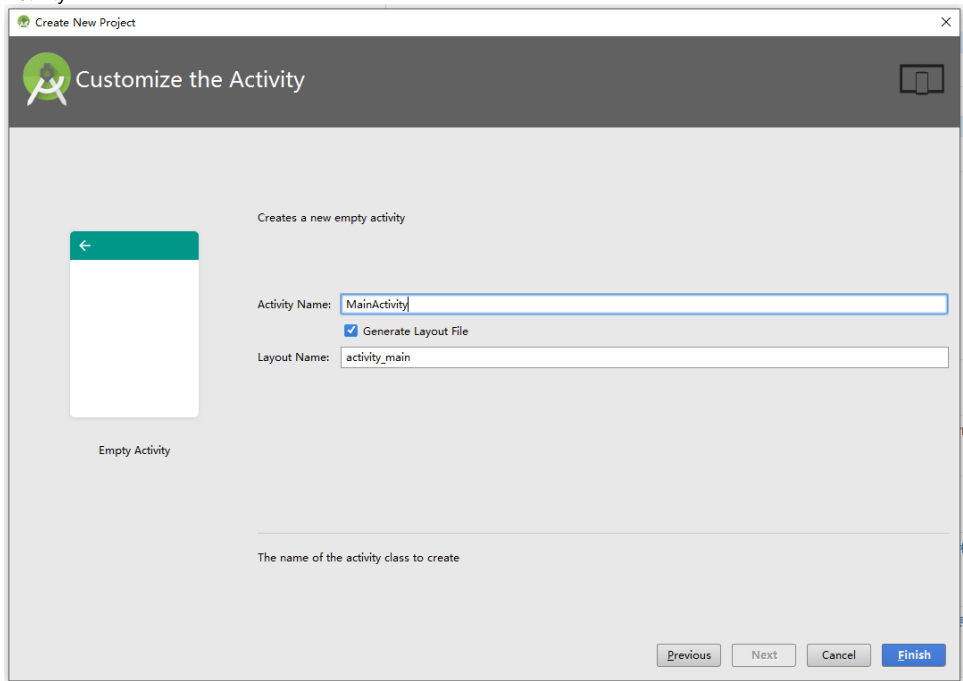
- Phone and Tablet**
 - Minimum SDK: API 18: Android 4.3 (Jelly Bean)
 - Lower API levels target more devices, but have fewer features available.
 - By targeting API 18 and later, your app will run on approximately 76.9% of the devices that are active on the Google Play Store.
 - [Help me choose](#)
- Wear**
 - Minimum SDK: API 21: Android 5.0 (Lollipop)
- TV**
 - Minimum SDK: API 21: Android 5.0 (Lollipop)
- Android Auto**
- Glass**
 - Minimum SDK: [Empty dropdown]

At the bottom left, there is a note: [#] Looking for SDKs available for download... At the bottom right, there are four buttons: 'Previous', 'Next' (highlighted in blue), 'Cancel', and 'Finish'.

4. ActivityEmpty ActivityNext;

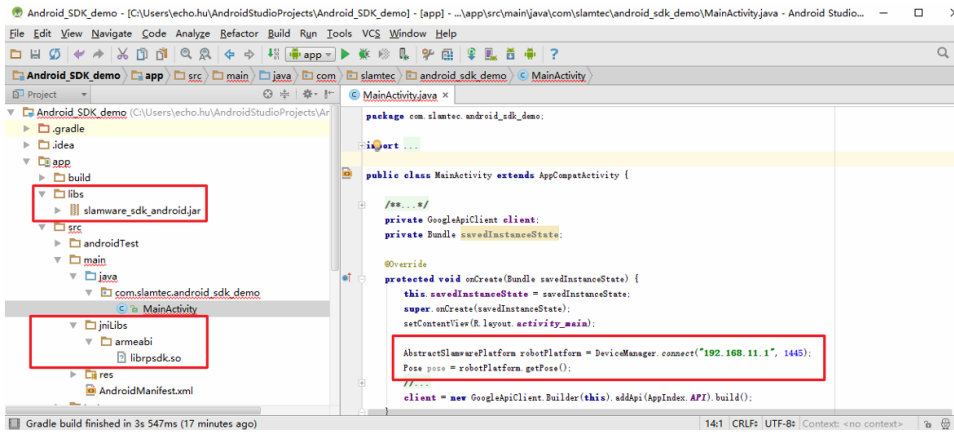


5. Activity



Hello World

1. SDkslamtec_agent.jararmeabi



2. SDP

1. ARMx86

2.

| | |
|-------------------------------------|----------|
| com.slamtec.slamware | slamware |
| com.slamtec.slamware.action | |
| com.slamtec.slamware.discovery | |
| com.slamtec.slamware.FirmwareUpdate | |
| com.slamtec.slamware.geometry | geometry |
| com.slamtec.slamware.robot | robot |
| com.slamtec.slamware.exceptions | |
| com.slamtec.slamware.message | message |
| com.slamtec.slamware.sdp | SDP |

| | |
|---------------------------------------|-------------------------------|
| AbstractDiscover | , abstract discover interface |
| AbstractDiscover.BleConfigureListener | , BleConfigureListener |
| AbstractDiscover.DiscoverStatus | DiscoverStatus |
| AbstractDiscover.DiscoveryListener | DiscoveryListener |

| | |
|--------------------------|------------|
| AbstractSlamwarePlatform | SLAMWARE |
| ActionStatus | |
| BleDevice | BleDevice |
| CompositeMapHelper | |
| Device | |
| DeviceManager | |
| DepthCameraFrame | |
| DiscoveryMode | |
| FirmwareUpdateInfo | |
| FirmwareUpdateProgress | |
| HealthInfo | |
| HealthInfo.BaseError | |
| IAction | |
| IMoveAction | |
| ImpactSensorInfo | |
| ImpactSensorType | |
| ImpactSensorValue | |
| ISweepMoveAction | |
| LaserPoint | |
| LaserScan | |
| Line | |
| Location | 3D |
| Map(Robot) | |
| Map(SDP) | SDP |
| MapKind | |
| MapLayer | |
| MapType | |
| MdnsDevice | MdnsDevice |
| MoveDirection | |

| | |
|-----------------------------|----------------------------|
| NetworkMode | |
| Path | |
| PointF | 2D |
| PointMap | |
| Pose | |
| PoseMap | PoseMap |
| RecoverLocalizationMovement | |
| RecoverLocalizationOptions | |
| RestartMode | |
| Rotation | |
| SensorType | |
| Size | Size |
| SlamwareCorePlatform | Abstract Slamware Platform |
| SlamwareSdpPlatform | SDP |
| SlamcoreShutdownParam | |
| SleepMode | |
| SystemParameters | |

com.slamtec.slamware

AbstractSlamwarePlatform

Abstract Slamware Platform SLAMWARE

SlamwareCorePlatform

AbstractSlamwarePlatform()

AbstractSlamwarePlatformDeviceManagerAbstractSlamwarePlatform

addWall(Line wall)

SLAMWARE

| | |
|------|--|
| | |
| wall | |

```
addWalls(java.util.List<Line> walls)
```

SLAMWARE

| | |
|-------|--|
| | |
| walls | |

```
clearMap()
```

```
clearWallById(int id)
```

```
(id idAbstractSlamwarePlatform.getLines(ArtifactUsage var1)line id)
```

| | |
|----|----|
| | |
| id | id |

```
clearWalls()
```

Slamware

```
configureNetwork(int mode, java.util.HashMap<java.lang.String,java.lang.String> options)
```

Slamware Coreboolean

| | |
|---------|--|
| | |
| mode | |
| options | |

| | |
|---------|--|
| | |
| AP | Slamware CoreWiFiWifiWiFiDHCP192.168.11.1Slamware Core |
| Station | Slamware CoreWiFiWifiSlamware CoreHigh Speed BusIP |
| Disable | Slamware CoreIPDNSAPI |

- Slamware CoreAP

```
Platform.configureNetwork(NetworkMode.NetworkModeAp, new HashMap<String, String>());
```

- Slamware CoreSlamtecAP

```
HashMap<String, String> options = newHashMap<String, String>(); options.put("ssid", "Slamtec"); options.put("password", "Password"); platform.configureNetwork(NetworkMode.NetworkModeStation, options);
```

- Slamware CoreIP192.168.12.13192.168.12.1DNS114.114.114.114

```
HashMap<String, String> options = newHashMap<String, String>(); options.put("ip", "192.168.12.13"); options.put("mask": "255.255.255.0"); options.put("gateway": "192.168.12.1"); options.put("dns": "114.114.114.114"); platform.configureNetwork(NetworkMode.NetworkModeDisabled, options);
```


disconnect()

getAvailableMaps()

SLAMWARE

getBatteryIsCharging()

getBatteryPercentage()

0-100

getCurrentAction()

getDCIsConnected()

getDeviceId()

UUIDString

getFirmwareUpdateInfo()

FirmwareUpdateInfo

getFirmwareUpdateProgress()

FirmwareUpdateProgress

getHardwareVersion()

string

getKnownArea(MapType type)

type –

getKnownArea(MapType type, MapKind kind)

| | |
|------|--|
| | |
| type | |
| kind | |

getLaserScan()

LASERLASER

getLocalizationQuality()

getLocation()

getManufacturerId()

idint

getManufacturerName()

string

getMap(MapType type, MapKind kind, android.graphics.RectF area)

SLAMWARE

| | |
|------|--|
| | |
| type | |
| kind | |
| area | |

getMapLocalization()

SLAMWARESLAMWARE

getMapUpdate()

SLAMWARESLAMWARE

getModelId()

idint

getModelName()

string

getNetworkStatus()

string

getPose()

getRobotHealth()

getSDKVersion()

SLAMWARE SDKSLAMWARESDK

getSlamwareVersion()

SLAMWARESLAMWARE

getSoftwareVersion()

getSystemParameter(java.lang.String param)

| | |
|-------|--|
| | |
| param | |

getWalls()

goHome()

moveBy(MoveDirection direction)

MoveAction.cancel()moveBy

| | |
|-----------|--|
| | |
| direction | |

```
moveTo(java.util.List<Location> locations)
```

| | |
|-----------|--|
| | |
| locations | |

```
moveTo(java.util.List<Location> locations, boolean appending)
```

| | |
|-----------|----------|
| | |
| locations | |
| appending | SLAMWARE |

```
moveTo(java.util.List<Location> locations, boolean appending, boolean isMilestone)
```

| | |
|-------------|-------------------|
| | |
| locations | |
| appending | SLAMWARE |
| isMilestone | SLAMWAREtruefalse |

```
moveTo(Location location)
```

| | |
|----------|--|
| | |
| location | |

```
moveTo(Location location, boolean appending)
```

| | |
|-----------|----------|
| | |
| location | |
| appending | SLAMWARE |

```
moveTo(Location location, boolean appending, boolean isMilestone)
```

| | |
|-------------|-------------------|
| | |
| location | |
| appending | SLAMWARE |
| isMilestone | SLAMWAREtruefalse |

restartModule()

SLAMWARE

restartModule(RestartMode mode)

SLAMWARE

| | |
|------|----------|
| | |
| mode | SLAMWARE |

rotate(Rotation rotation)

| | |
|----------|--|
| | |
| rotation | |

rotateTo(Rotation orientation)

| | |
|-------------|--|
| | |
| orientation | |

searchPath(Location location)

| | |
|----------|--|
| | |
| location | |

setMap(Map map)

SLAMWAREsetPosemoveto

| | |
|-----|--|
| | |
| map | |

setMap(Map map, MapType type)

SLAMWAREsetPose

| | |
|------|--|
| | |
| map | |
| type | |

setMap(Map map, MapType type, MapKind kind)

SLAMWAREsetPose

| | |
|------|--|
| | |
| map | |
| type | |
| kind | |

setMapLocalization(boolean v)

| | |
|---|----------|
| | |
| v | SLAMWARE |

setMapUpdate(boolean v)

| | |
|---|----------|
| | |
| v | SLAMWARE |

setPose(Pose pose)

| | |
|------|--|
| | |
| pose | |

setSystemParameter(java.lang.String param, java.lang.String value)

| | |
|-------|--|
| | |
| param | |
| value | |

startFirmwareUpdate()

boolean

startSweep()

SLAMWARE Core

sweepSpot(Location location)

SLAMWARE Core

ArtifactUsage

ArtifactUsageVirtualWall

ArtifactUsageVirtualTrack

```
List<Line> getLines(ArtifactUsage usage)
```

```
line
```

| | |
|-------|--|
| | |
| usage | |

```
boolean addLine(ArtifactUsage usage, Line line)
```

```
boolean addLines(ArtifactUsage usage, List<Line> lines)
```

```
idArraylist<Line> lines = AbstractSlamwarePlatform.getLines(ArtifactUsage usage);
```

```
boolean removeLineById(ArtifactUsage usage, int id)
```

```
boolean clearLines(ArtifactUsage usage)
```

```
PowerStatus getPowerStatus()
```

```
void wakeUp()
```

```
IMoveAction recoverLocalization(RectF area)
```

```
area20*20
```

```
PointPDF getAuxLocation()
```

```
getAuxLocation()recoverLocalization
```

```
auto locationPdf = platform. getAuxLocation();  
Location location = locationPdf.location;  
float distant = locationPdf.circular_error_probability;  
area((location.x() - distant), (location.y() - distant), 2*distant, 2*distant);RectangleF  
auto act = platform. recoverLocalization(area);  
act.waitUntilDone();
```

```
CompositeMap getCompositeMap()
```

```
void setCompositeMap(CompositeMap map, Pose pose)
```

```
Pose getHomePose()
```

```
(0,0)
```

```
List<ImpactSensorInfo> getSensors()
```

```
list
```

```
HashMap<Integer, ImpactSensorValue> getSensorValues()
```

HashMap

ImpactSensorValue getSensorValue(Integer var1)

key

IMoveAction moveTo(Location location, MoveOption option, float yaw)

location moveOption

| appending | boolean | SLAMWARE |
|---------------------------|---------|--|
| milestone | boolean | SLAMWAREtruefalse |
| noSmooth | boolean | |
| keyPoints | boolean | |
| precise | boolean | |
| withYaw | boolean | |
| yaw | float | |
| returnUnreachableDirectly | boolean | true |
| trackWithOA | boolean | trackWithOA true,.(,trackWithOA true,) |
| speedRatio | Double | ,01,(moveBy |

IMoveAction moveTo(java.util.List locations, MoveOption option, float yaw)

publishDepthCamFrame(int sensorId,DepthCameraFrame depthCameraFrame)

sensorId sensorId, depthCameraFrame

com. slamtec slamware action

IAction

IMoveAction, ISweepMoveAction

cancel()

getActionName()

string

getProgress()

0~1double

getStatus()

waitUntilDone()

boolean isEmpty()

```
int getActionId()
```

```
id
```

```
String getReason()
```

```
actionnull0"failed"action, "aborted"action(cancelactionaction)  
moveToaction"unreachable")
```

IMoveAction IAction

```
IAction
```

```
IAction
```

```
ISweepMoveAction
```

```
getRemainingMilestones()
```

```
getRemainingPath()
```

```
com.slamtec.slamware.action.IAction
```

```
cancel, getActionName, getProgress, getStatus, waitUntilDone
```

ISweepMoveAction

```
pause()
```

```
resume()
```

ISweepMoveAction IAction

```
IMoveAction
```

```
IAction, IMoveAction
```

```
com.slamtec.slamware.action.IMoveAction
```

```
getRemainingMilestones, getRemainingPath
```

```
com.slamtec.slamware.action.IAction
```

```
cancel, getActionName, getProgress, getStatus, waitUntilDone
```

path

```
Path()
```

```
Path
```

```
Path(Path path)
```


pathPath

Path(java.util.Vector<Location> points)

pointsPath

getPoints()

setPoints(java.util.Vector<Location> points)

ActionStatus

public enum ActionStatus, java.lang.Enum<ActionStatus>,

WAITING_FOR_START

RUNNING

FINISHED

PAUSED

STOPPED

ERROR

MoveDirection

public enum MoveDirection, java.lang.Enum<MoveDirection>,

FORWARD

BACKWARD

TURN_RIGHT

TURN_LEFT

com.slamtec.slamware.discovery

AbstractDiscover.BleConfigureListener

AbstractDiscover

```
onConfigureSuccess()
```

```
onConfigureFailure(java.lang.String error)
```

String error

```
BLE_CONFIG_ERROR_BLE_DISCONNECTED
```

```
BLE_CONFIG_ERROR_WRITTING_FAIL
```

```
BLE_CONFIG_ERROR_SSID_REQUIRED
```

```
SSID
```

```
BLE_CONFIG_ERROR_UNABLE_CONNECT_WIFI
```

```
WiFi
```

```
BLE_CONFIG_ERROR_INVALID_PWD
```

AbstractDiscover

```
public abstract class AbstractDiscover, abstract discover
```

```
DeviceManager
```

```
AbstractDiscover.BleConfigureListener
```

```
AbstractDiscover.DiscoverStatus
```

```
AbstractDiscover.DiscoveryListener
```

```
AbstractDiscover()
```

```
AbstractDiscover
```

```
getMode()
```

```
setListener(AbstractDiscover.DiscoveryListener listener)
```

```
listener
```

```
getStatus(DiscoveryMode mode)
```

```
start(DiscoveryMode mode)
```

```
stop(DiscoveryMode mode)
```

AbstractDiscover.DiscoveryListener

```
AbstractDiscover
```

DiscoveryListener()

DiscoveryListener

onStartDiscovery(AbstractDiscover discover)

Discovery

onStopDiscovery(AbstractDiscover discover)

Discovery

onDiscoveryError(AbstractDiscover discover, java.lang.String error)

Discovery

onDeviceFound(AbstractDiscover discover, Device device)

BleDevice

Device

BleDevice(BluetoothDevice device)

BleDevice

getDevice()

device

canBeFoundWith(DiscoveryMode mode)

discovery

Device canBeFoundWith

Device

public abstract class Device,

BleDevice, MdnsDevice

Device()

Device

getManufactureId()

Manufacture id

setManufactureId(int manufactureId)

manufacture id

getModelId()

model id

```
setModelId(int modelId)
mode id
getManufactureName()
manufacture name
setManufactureName(java.lang.String manufactureName)
manufacture name
getModelName()
mode name
setModelName(java.lang.String modelName)
mode name
getHardwareVersion()
hard ware version
setHardwareVersion(int hardwareVersion)
hardware version
getSoftwareVersion()
software version
setSoftwareVersion(int softwareVersion)
software version
getSerialNumber()
serial number
setSerialNumber(java.lang.String serialNumber)
serial number
canBeFoundWith(DiscoveryMode mode)
discovery
getDeviceId()
device id
setDeviceId(java.util.UUID deviceId)
device id
getDeviceName()
device name
setDeviceName(java.lang.String deviceName)
device name
```

DeviceManager

AbstractDiscover

The manager to manage devices

Nested classes/interfaces inherited from class

com.slamtec.slamware.discovery.AbstractDiscover:

AbstractDiscover.BleConfigureListener,

AbstractDiscover.DiscoverStatus,

AbstractDiscover.DiscoveryListener

DeviceManager(Context context)

DeviceManager

connect(java.lang.String host, int port)

SLAMWARE CoreAndroidSLAMWARE Core

| | |
|------|--------------|
| | |
| host | 192.168.11.1 |
| port | |

connect(Device device)

SLAMWARE

| | |
|--------|--|
| | |
| device | |

pair(Device device, java.lang.String wifiSSID, java.lang.String wifiPassword, AbstractDiscover.
BleConfigureListener listener)

SSIDSLAMWARE

| | |
|--------------|----------|
| | |
| device | |
| wifiSSID | WiFiSSID |
| wifiPassword | WiFi |
| listener | |

setListener(AbstractDiscover.DiscoveryListener listener)

AbstractDiscover setListener

getStatus(DiscoveryMode mode)

AbstractDiscovergetStatus

start(DiscoveryMode mode)

AbstractDiscoverstart

stop(DiscoveryMode mode)

AbstractDiscoverstop

getMode()

AbstractDiscovergetMode

MdnsDevice

Device

MdnsDevice(java.lang.String addr, int port)

MdnsDevice

```
getAddr()
```

```
getPort()
```

```
canBeFoundWith(DiscoveryMode mode)
```

```
DevicecanBeFoundWith
```

AbstractDiscover.DiscoverStatus

```
AbstractDiscover
```

```
STOPPED
```

```
WORKING
```

```
ERROR
```

DiscoveryMode

```
BLE
```

```
BLE
```

```
MDNS
```

```
mdns
```

com.slamtec.slamware.FirmwareUpdate

FirmwareUpdateInfo

```
public class FirmwareUpdateInfo
```

```
FirmwareUpdateInfo(java.lang.String current, java.lang.String latest, java.lang.String releaseDate, java.lang.String brief)
```

```
FirmwareUpdateInfo(current/latest/releasedDate/brief
```

```
getBrief()
```

```
, string
```

```
getCurrent()
```

```
, string
```

```
getLatest()
```

, string

getReleaseDate()

, string

FirmwareUpdateProgress

public class FirmwareUpdateProgress

FirmwareUpdateProgress(int currentStep, int totalStep, int currentStepProgress, java.lang.String currentStepName)

FirmwareUpdateProgresscurrentStep/totalStep/currentStepProgress/currentStepName

getCurrentStep()

int

getCurrentStepName()

string

getCurrentStepProgress()

int

getTotalStep()

int

com.slamtec.slamware.geometry

Line

public class Line,

Line(int segmentId, PointF startPoint, PointF endPoint)

Linesegment idstart pointend point

Line(int segmentId, float startX, float startY, float endX, float endY)

Line segment id, startX, startY, endX, endY

Line(Line line)

Line Line

Line(PointF startP, PointF endP)

Line startPendP

getStartPoint()

setStartPoint(PointF startPointF)

getEndPoint()

setEndPoint(PointF endPoint)

```
getStartX()  
start x  
getStartY()  
star y  
getEndX()  
end x  
getEndY()  
end y  
getSegmentId()  
segment id  
setSegmentId(int segmentId)  
Segment id
```

PointF

```
public class PointF,2d
```

```
PointF()  
PointF  
PointF(float x, float y)  
PointFxy  
PointF(PointF rhs)  
PointFPointF
```

```
getX()  
X  
setX(float x)  
X  
getY()  
Y  
setY(float y)  
Y
```

Size

```
public class Size size
```

```
Size()  
Size  
Size(int width, int height)  
Sizewidthheight  
Size(Size rhs)
```


SizeSize

getWidth()

width

setWidth(int width)

width

getHeight()

height

setHeight(int height)

height

com.slamtec.slamware.robot

HealthInfo

public class HealthInfo

HealthInfo.BaseError

HealthInfo()

HealthInfo()

HealthInfo(boolean warning, boolean error, boolean fatal, java.util.ArrayList<HealthInfo.BaseError> errors)

HealthInfo()warning/error/fatal/

getErrors()

isError()

Boolean

isFatal()

Boolean

isWarning()

Boolean

setError(boolean error)

| | |
|-------|--|
| | |
| error | |

setErrors(java.util.ArrayList<HealthInfo.BaseError> errors)

| | |
|--|--|
| | |
|--|--|

| | |
|--------|--|
| | |
| errors | |

setFatal(boolean fatal)

| | |
|-------|--|
| | |
| fatal | |

setWarning(boolean warning)

| | |
|---------|--|
| | |
| warning | |

HealthInfo.BaseError

HealthInfo

Fields

BaseErrorLevelHealthy

BaseErrorComponentMotion

BaseErrorComponentPower

BaseErrorComponentSensor

BaseErrorComponentSystem

BaseErrorComponentUnknown

BaseErrorComponentUser

BaseErrorLevelError

BaseErrorLevelFatal

BaseErrorLevelUnknown

BaseErrorLevelWarn

BaseComponentErrorTypeUnknown

BaseComponentErrorTypeUser

BaseComponentErrorTypeSystemNone

()

BaseComponentErrorTypeSystemEmergencyStop

BaseComponentErrorTypeSystemTemperatureHigh

BaseComponentErrorTypeSystemTemperatureLow

BaseComponentErrorTypeSystemWatchDogOverflow

BaseComponentErrorTypeSystemCtrlBusDisconnected

BaseComponentErrorTypeSystemSlamwareRebooted

slamware

BaseComponentErrorTypePowerNone

()

BaseComponentErrorTypePowerControllerDown

BaseComponentErrorTypePowerPowerLow

BaseComponentErrorTypePowerOverCurrent

BaseComponentErrorTypeMotionNone

()

BaseComponentErrorTypeMotionControllerDown

BaseComponentErrorTypeMotionMotorAlarm

BaseComponentErrorTypeMotionMotorDown

BaseComponentErrorTypeMotionOdometryDown

BaseComponentErrorTypeMotionBrushStall

()

BaseComponentErrorTypeMotionBlowerStall

BaseComponentErrorTypeSensorNone

BaseComponentErrorTypeSensorControllerDown

BaseComponentErrorTypeSensorBumperDown

BaseComponentErrorTypeSensorCliffDown

BaseComponentErrorTypeSensorSonarDown

BaseComponentErrorTypeSensorDustbinBlock

()

BaseComponentErrorTypeSensorDustbinGone

()

BaseComponentErrorTypeSensorWallIrDown

()

BaseComponentErrorTypeSensorMagTapeTriggered

BaseComponentErrorTypeSensorMagSelfTestFailed

BaseError()

BaseError

BaseError(int id, int errorCode, int errorLevel, int errorComponent, int componentErrorCode, java.lang.String errorMessage)

BaseError

| error code | |
|--------------------|--|
| error level | |
| error component | |
| componentErrorCode | |
| errorMessage | |

getComponentErrorCode()

```
int
getErrorCode()

int
getErrorComponent()

int
getErrorLevel()

int
getErrorMessage()

string
getId()

idint
setComponentErrorCode(int componentErrorCode)

int
setErrorCode(int errorCode)

int
setErrorComponent(int errorComponent)

int
setErrorLevel(int errorLevel)

int
setErrorMessage(java.lang.String errorMessage)

string
setId(int id)

ldldint
```

LaserPoint

```
public class LaserPoint,
```

```
LaserPoint()
```

```
LaserPoint
```

```
LaserPoint(float distance, float angle)
```

```
LaserPoint
```

```
LaserPoint(float distance, float angle, boolean valid)
```

```
LaserPoint
```

```
LaserPoint(LaserPoint rhs)
```

```
LaserPointLaserPoint
```

```
getDistance()
```

```
setDistance(float distance)
```

```
getAngle()
```

```
setAngle(float angle)
```

```
isValid()
```

```
setValid(boolean valid)
```

LaserScan

```
public class LaserScan
```

```
LaserScan()
```

```
LaserScan
```

```
LaserScan(java.util.Vector<LaserPoint> laserPoints)
```

```
LaserScanLaserPoints
```

```
LaserScan(java.util.Vector<LaserPoint> laserPointsPose pose)
```

```
LaserScanLaserPointPose
```

```
LaserScan(LaserScan rhs)
```

```
LaserScanLaserScan
```

```
getLaserPoints()
```

```
setLaserPoints(java.util.Vector<LaserPoint> laserPoints)
```

```
getPose()
```

```
setPose(Pose pose)
```

Location

```
public class Location3d
```

```
Location()
```

```
Location
```

```
Location(float x, float y, float z)
```

```
Locationxyz
```

```
Location(Location rhs)
```

```
LocationLocation
```

```
distanceTo(Location that)
```

```
Location
```

```
getX()  
X  
setX(float v)  
X  
getY()  
Y  
setY(float v)  
Y  
getZ()  
Z  
setZ(float v)  
Z
```

Map

```
public class Map
```

```
Map(PointF origin, Size dimension, PointF resolution, long timestamp, byte[] data)
```

```
Map
```

```
getOrigin()
```

```
origin
```

```
setOrigin(PointF origin)
```

```
origin
```

```
getDimension()
```

```
dimension
```

```
setDimension(Size dimension)
```

```
dimensions
```

```
getResolution()
```

```
resolution
```

```
setResolution(PointF resolution)
```

```
resolution
```

```
getTimestamp()
```

```
time stamp
```

```
setTimestamp(long timestamp)
```

```
time stamp
```

```
getMapArea()
```

```
map area
```

```
getData()
```

```
data
```

```
setData(byte[] data)
```

```
data
```

NetworkMode

Fields

NetworkModeAP

AP

NetworkModeStation

Station

NetworkModeWifiDisabled

Wifi

NetworkMode()

NetworkMode()

Pose

public class Pose

Pose()

Pose

Pose(Location loc, Rotation rot)

Poselocros

Pose(float x, float y, float z, float yaw, float roll, float pitch)

Posexyzyawrollpitch

Pose(Pose rhs)

PosePose

Location getLocation()

Location

setLocation(Location location)

Location

getRotation()

rotation

setRotation(Rotation rotation)

rotation

getX()

X

setX(float v)

X

getY()

Y

setY(float v)

Y

getZ()

Z


```
setZ(float v)
Z
getYaw()
yaw
setYaw(float v)
yaw
getRoll()
roll
setRoll(float v)
roll
getPitch()
pitch
setPitch(float v)
pitch
```

Rotation

```
public class Rotation
```

```
Rotation()
```

```
Rotation
```

```
Rotation(float yaw)
```

```
Rotationyaw
```

```
Rotation(float yaw, float pitch, float roll)
```

```
Rotationyawpitchroll
```

```
Rotation(Rotation rhs)
```

```
RotationRotation
```

```
getYaw()
```

```
yaw
```

```
setYaw(float yaw)
```

```
Yaw
```

```
getRoll()
```

```
roll
```

```
setRoll(float roll)
```

```
roll
```

```
getPitch()
```

```
pitch
```

```
setPitch(float pitch)
```

```
pitch
```

SystemParameters

```
SystemParameters()
```

```
SystemParameters
```

Fields

```
SYSPARAM_ROBOT_SPEED
```

```
SYSVAL_ROBOT_SPEED_HIGH
```

```
SYSVAL_ROBOT_SPEED_MEDIUM
```

```
SYSVAL_ROBOT_SPEED_LOW
```

SleepMode

```
Unknown
```

```
Slamware
```

```
Awake
```

```
,
```

```
WakingUp
```

```
(wakeup())
```

```
Asleep
```

```
„wakeup()WakingUp,Awake
```

DockingStatus

```
Unknown
```

```
DockingSlamware
```

```
OnDock
```

```
NotOnDock
```

PowerStatus

```
public PowerStatus(boolean isDCConnected, DockingStatus dockingStatus, boolean isCharging,int batteryPercentage,  
SleepMode sleepMode)
```

```
public boolean isDCConnected()
```

```
public DockingStatus getDockingStatus()
```

Docking

```
public boolean isCharging()
```

```
public int getBatteryPercentage()
```

0-100

```
public SleepMode getSleepMode()
```

GridMap

```
public Location getOrigin()
```

```
public void setOrigin(Location origin)
```

```
public Size getDimension()
```

grid

```
public void setDimension(Size dimension)
```

grid

```
public PointF getResolution()
```

grid

```
public void setResolution(PointF resolution)
```

grid

```
public byte[] getMapData()
```

grid

```
public void setMapData(byte[] mapData)
```

grid

```
public void clear()
```

grid

CompositeMap

```
public CompositeMap()
```

```
public CompositeMap(CompositeMap another)
```

```
public MapMetaData getMetaData()
```

Composite map

```
public void setMetaData(MapMetaData data)
```

Composite map

```
public ArrayList<MapLayer> getMaps()
```

Composite map

```
public void setMaps(ArrayList<MapLayer> maps)
```

Composite map

MapKind

EXPLORE_MAP

SLAM

SWEEP_MAP

UWB_MAP

UWB

MapType

BITMAP_8BIT

8bit integer

MapLayer

MapLayer()

MapLayer

getMetaData()

getName()

getUsage()

clear()

PoseMap

MapLayer

PoseMap()

PoseMap

getPoses()

Poses map

setPoses()

Poses map

PointMap

PointMap()

PointMap

PointMap(java.util.List points, long timestamp)

pointtimeStamp

getMapArea()

rectF

getPoints()

setPoints()

RecoverLocalizationMovement

Unknown

NoMove

RotateOnly

Any

RecoverLocalizationOptions

RecoverLocalizationOptions()

RecoverLocalizationOptions

getMaxRecoverTimeInMilliseconds()

setMaxRecoverTimeInMilliseconds(Integer maxRecoverMS)

setRecoverMovementType(RecoverLocalizationMovement movementType)

movement

RecoverLocalizationMovement getRecoverMovementType()

movement

SensorType

Bumper

Cliff

Sonar

DepthCamera

WallSensor

SlamcoreShutdownParam

SlamcoreShutdownParam()

SlamcoreShutdownParam

int getRestartTimeIntervalMinute()

setRestartTimeIntervalMinute(int restartTimeIntervalMinute)

SleepMode

Unknown

Awake

,

WakingUp

(wakeup())

Asleep

„wakeup()WakingUp,Awake

RestartMode

SOFT

HARD

LineMap

```
public HashMap<String, CompositeLine> getLines()  
line map  
public void setLines(HashMap<String, CompositeLine> lines)  
line map  
public void clear()  
line map
```

PointsMap

```
public ArrayList<PointPDF> getPoints()  
points map  
public void setPoints(ArrayList<PointPDF> points)  
points map  
public void clear()  
points map
```

ImpactSensorInfo

```
ImpactSensorInfo(int sensorId, Pose pose, ImpactSensorType type, SensorType coreSensorType, float refreshFreq)
```

ImpactSensorInfo

```
getSensorId()
```

id

```
getPose()
```

```
getKind()
```

```
getType()
```

ImpactSensorType

Digital

Analog

ImpactSensorValue

ImpactSensorValue(long time, float value)

timevalue

getTime()

getValue()

com.slamtec.slamware.exceptions

AlreadyConnectedException

"Already Connected to the device"

ConnectionFailException

"Connection Failed"

ConnectionLostException

"Connection Lost"

ConnectionTimeOutException

"Connection Time Out"

InvalidArgumentException

"Invalid Argument"

OperationFailException

"Operation Failed"

OutOfResourceException

"Out of Resource"

ParseInvalidException

"Failed to parse device data"

PathFindFailException

"Failed to find path"

RequestFailException

"Request Failed"

RequestTimeOutException

"Request Time Out"

UnauthorizedRequestException

"Unauthorized request"

UnsupportedCommandException

"Unsupported Command"

com.slamtec.slamware.message

DepthCameraFrame

```
DepthCameraFrame()
```

```
DepthCameraFrame
```

```
setMinValidDistance(float minValidDistance)
```

```
float getMinValidDistance()
```

```
setMaxValidDistance()
```

```
float getMaxValidDistance()
```

```
setMinFovPitch(float MinFovPitch)
```

```
float getMinFovPitch()
```

```
setMaxFovPitch(float MaxFovPitch)
```

```
float getMaxFovPitch()
```

```
setMinFovYaw(float MinFovYaw )
```

```
float getMinFovYaw()
```

```
setMaxFovYaw(float MaxFovYaw)
```

```
float getMaxFovYaw()
```

```
setCols(int cols)
```

```
int getCols()
```

```
setRows(int rows)
```

```
int getRows()
```

```
setData(ArrayList<Float> data)
```

```
*cols*rows float
```

```
ArrayList<float> getData()
```

```
*cols*rows float
```

com.slamtec.slamware.sdp

Action

IAction

```
cancel()
```

```
getActionName()
```

string

```
getProgress()
```

0~1double

```
getStatus()
```

```
waitUntilDone()
```

```
isEmpty()
```

action

```
getActionId()
```

actionid

```
String getActionName()
```

action

```
String getReason()
```

actionnull0

"failed"action

```
"aborted"action(cancelactionaction)
```

"unreachable"()

```
"unhealthy",getRobotHealth(
```

```
"lifted",,"low_localization_quality"
```

```
moveToMoveOptionFlagKeyPointsflag,moveto:
```

```
getReason("blocked[lidar;wall;contact;depth_camera;sonar;cliff"],."["",",",",",(),lidar:;wall:;contact:;depth_camera:;sonar:;cliff:
```

```
releaseCPointer()
```

CompositeMapHelper

```
CompositeMapHelper()
```

```
CompositeMapHelper
```

```
loadFile(String var1)
```

```
saveFile(String var1, CompositeMap var2)
```