

KBSW191227



Slamware coreSlamware CoreRoboStudio

[KBSW183102](#)

[KBSW180143 SLAMWARE SDK](#)

[Android SDK](#)

CompositeMap getCompositeMap()

Slamware CorecompositemapCompositeMapnull

void setCompositeMap(CompositeMap map, Pose pose)

compositemap mapSlamware Core(,)

CompositeMapHelper

1.loadFile(String var1)

var1var1CompositeMapnull

2.saveFile(String var1, CompositeMap var2)

CompositeMapvar2var1StringnullString(SD)

1.SD

SD

```
RxPermissions rxPermission = new RxPermissions(this);
rxPermission.request(Manifest.permission.WRITE_EXTERNAL_STORAGE, Manifest.permission.READ_EXTERNAL_STORAGE).
subscribe(granted -> {
    if (granted) {}
    else
    {
        // permission denied
        Toast.makeText(this, "LogSD", Toast.LENGTH_SHORT).show();
        finish();
    }
});
```

2.Slamware Core

```
String originMap = Environment.getExternalStorageDirectory() + "/test/map/" + "originMap.stcm";
CompositeMapHelper compositeMapHelper = new CompositeMapHelper();
CompositeMap compositeMap1 = compositeMapHelper.loadFile(originMap);
Pose pose=new pose();
robotPlatform.setCompositeMap(compositeMap1,pose);
```

3.composite mapPOI

POI

```
// PoseMapPOI
PoseMap poseMap = new PoseMap();
poseMap.setUsage("point_of_interest");

// 10CompositePosePoseMap
HashMap<String, CompositePose> poseHashMap = new HashMap<>();
for (int i = 0; i < 10; i++)
{
    CompositePose compositePose = new CompositePose();
    compositePose.setName("point1" + i);
    compositePose.setPose(new Pose(new Location(i, i, 0), new Rotation()));
    poseHashMap.put("key1" + i, compositePose);
}
poseMap.setPoses(poseHashMap);

// PIOCompositeMap1
ArrayList<MapLayer> newMaps = compisteMap.getMaps();
newMaps.add(poseMap);
compositeMap1.setMaps(newMaps);
```

4.composite mapPOI

POI

```
//compositeMap1MapLayerUsage
ArrayList<MapLayer> maps = compositeMap1.getMaps();
Iterator itor = maps.iterator();
while (itor.hasNext())
{
    MapLayer mapLayer = (MapLayer) itor.next();
    Log.d(TAG, "mapLayer.getUsage(): " + mapLayer.getUsage());

    // point_of_interestposename;
    if (mapLayer.getUsage().equals("point_of_interest"))
    {
        Log.d(TAG, "point_of_interest: ");
        PoseMap poiMap = (PoseMap) mapLayer;
        HashMap poses = poiMap.getPoses();

        Iterator<HashMap.Entry<String, CompositePose>> iterator = poses.entrySet().iterator();
        while (iterator.hasNext())
        {
            HashMap.Entry<String, CompositePose> entry = iterator.next();
            entry.getKey();
            Log.d(TAG, "entry.getValue(): " + entry.getValue().getPose().getLocation().getX() + "
"+ entry.getValue().getPose().getLocation().getY() );
        }
    }
}
```

5.SD

```
//CompositeMap compositeMap = robotPlatform.getCompositeMap();

String addPOImap = Environment.getExternalStorageDirectory() + "/test/map/" + "addPOImap.stcm";
compositeMapHelper.saveFile(addPOImap, compositeMap1);
Log.d(TAG, "map save to " + addPOImap);
```