

KBSW183503 Android-

MoveToSpot, moveTo

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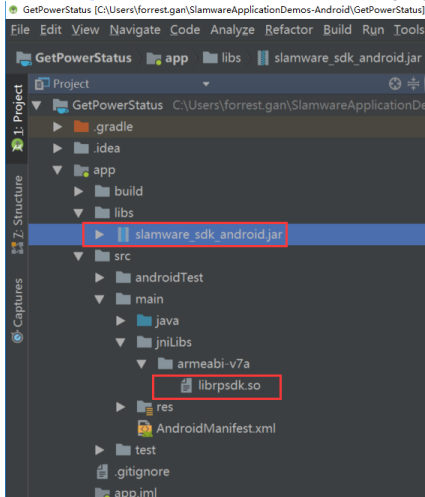
- - Android Studio 3.1.3
 - Slamware Android SDK: [slamware_sdk_android.2.6.0_rtm.20180820.tar.gz](#)
 - RoboStudio(): [Robostudio installer](#)
 - Sample Code:



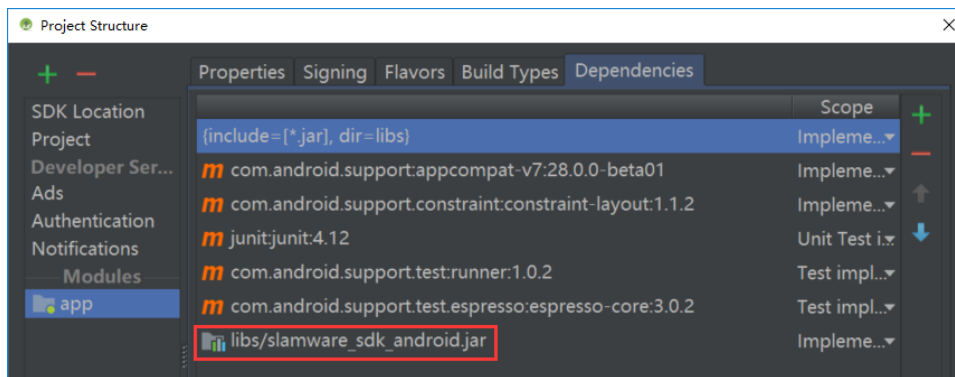
Android Studiobuild.gradleSlamware Android SDK 2.6.0 SDK slamware_sdk_android.jar librpsdk.so

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

1. MoveToSpot,libs slamware_sdk_android.jar jinLibs librpsdk.so SDK



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



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

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

4. AndroidWIFIshift + F10

 SDKAndroid

5. (0, 0, 0)-->(0, 1, 0) -->(1, 0, 0)-->(0, 0, 0)0, 0, 0(2, 1, 0(1.2f, 0, 0Robostuio
Your browser does not support the HTML5 video element

- IMvoveAction moveTo(Location location, boolean appending)locationappendingSLAMWARE
- (0, 0, 0)-->(0, 1, 0) -->(1, 0, 0)-->(0, 0, 0)0, 0, 0(2, 1, 0(1.2f, 0, 0

```

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

    try {
        MoveOption moveOption = new MoveOption();

        moveOption.setPrecise(true);
        moveOption.setMilestone(true);

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

        action = robotPlatform.moveTo(location3, moveOption, 0);
        action.waitForDone();

        action = robotPlatform.moveTo(location1, moveOption, 0);
        action.waitForDone();

        action = robotPlatform.moveTo(location2, moveOption, 0);
        action.waitForDone();

        action = robotPlatform.moveTo(location3, moveOption, 0);
        action.waitForDone();

        Log.d(TAG, "===== Virtual Track =====");
        /* draw a virtual track from (0, 0) to (2, 0), then move to (0, 0) via virtual track */
        robotPlatform.addLine(ArtifactUsageVirtualTrack, new Line(new PointF(0, 0), new PointF(2, 1)));

        moveOption.setKeyPoints(true);
        moveOption.setPrecise(true);
        action = robotPlatform.moveTo(new Location(1.2f, 0, 0), moveOption, 0);
        action.waitForDone();
        if (action.getStatus() == ActionStatus.ERROR) {
            Log.d(TAG, "Action Failed: " + action.getReason());
        }
    } catch (ConnectionTimeoutException e) {
        /* Exception Handle code*/
        ....
    }

```