


KBSW183505 Android-

[GetLaserScan](#) , [getLaserScan](#)

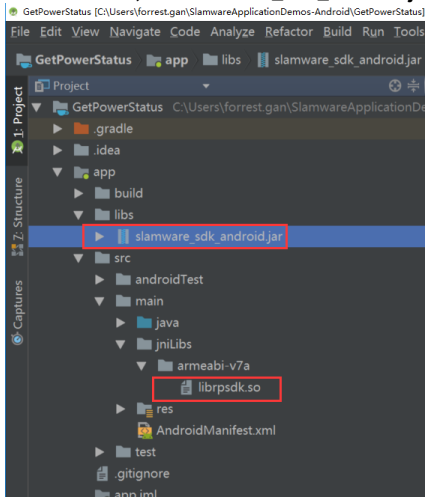
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- - Android Studio 3.1.3
 - Slamware Android SDK: [slamware_sdk_android.2.6.0_rtm.20180820.tar.gz](#)
 - RoboStudio():[Robostudio installer](#)
 - Sample Code:

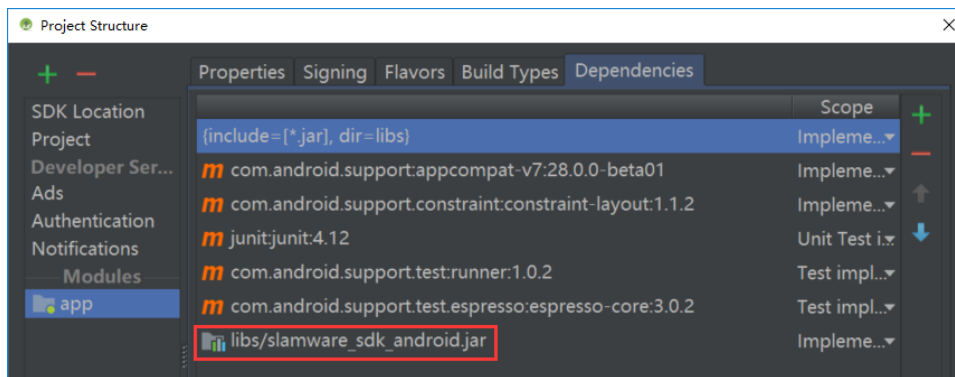
 Android Studiobuild.gradleSlamware Android SDK 2.6.0 SDK slamware_sdk_android.jar [librpsdk.so](#)

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

1. [GetLaserScan](#),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. Android Studio Logcat

```
HUAWEI BLN-AL10 Android com.slamtec.www.getlaserscan Verbose Q
08-29 15:28:24.572 20053-20053/com.slamtec.www.getlaserscan D/MainActivity: Angle: 1.8068349 Distan
Angle: 1.806143 Distance: 100000.0 is Valid: false
Angle: 1.7975404 Distance: 1.0789645 is Valid: true
Angle: 1.7971442 Distance: 100000.0 is Valid: false
Angle: 1.7885387 Distance: 1.0599309 is Valid: true
Angle: 1.7881444 Distance: 100000.0 is Valid: false
Angle: 1.7798264 Distance: 1.0377878 is Valid: true
Angle: 1.7788727 Distance: 100000.0 is Valid: false
Angle: 1.7698729 Distance: 100000.0 is Valid: false
Angle: 1.7683833 Distance: 1.0176743 is Valid: true
Angle: 1.7593834 Distance: 0.9999103 is Valid: true
Angle: 1.7504752 Distance: 0.98374534 is Valid: true
Angle: 1.7393162 Distance: 0.9657698 is Valid: true
Angle: 1.732373 Distance: 0.94585115 is Valid: true
Angle: 1.7248766 Distance: 100000.0 is Valid: false
Angle: 1.7212555 Distance: 0.93283564 is Valid: true
Angle: 1.7158768 Distance: 100000.0 is Valid: false
Angle: 1.7121408 Distance: 0.915742 is Valid: true
Angle: 1.7030251 Distance: 0.9027253 is Valid: true
Angle: 1.6939099 Distance: 0.8887834 is Valid: true
Angle: 1.6828558 Distance: 0.8777189 is Valid: true
Angle: 1.674012 Distance: 0.86374646 is Valid: true
Angle: 1.662473 Distance: 0.8518339 is Valid: true
Angle: 1.6553771 Distance: 0.8387217 is Valid: true
Angle: 1.6443474 Distance: 0.8288127 is Valid: true
```

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

LaserScan laserScan;
try {
    laserScan = robotPlatform.getLaserScan();

    /* Get Lidar scan data */
    Vector<LaserPoint> laserPoints = laserScan.getLaserPoints();

    /* print Laser data */
    for(int i=0; i<laserPoints.size(); i++) {
        Log.d(TAG, "Angle:      " + laserPoints.get(i).getAngle()
                + " Distance: " + laserPoints.get(i).getDistance()
                + " is Valid: " + laserPoints.get(i).isValid());
    }
}
} catch (ConnectionTimeoutException e) {
    /* Exception Handle code*/
    ....
}
```