Roboter Beispiel

**public** **void** RobotEndpointExample() **throws** InstantiationException, IllegalAccessException, IOException {

RobotEndpoint robotEnd = **new** RobotEndpoint();

robotEnd.open(9999);

robotEnd.addOnConnectionIncommingListener(**new** IConnectionIncommingEventHandler() {

@Override

**public** **void** OnNewConnection(Socket sock) {

System.***out***.println("Controller has connected: " + sock.getRemoteSocketAddress().toString());

}

});

robotEnd.addOnDisconnectListener(**new** IDisconnectedEventListener() {

@Override

**public** **void** OnDisconnect() {

System.***out***.println("Controller has disconnected");

}

});

robotEnd.addCommandListener(**new** ICommandReceiver() {

@Override

**public** **void** commandReceived(CommandBase cmd) {

System.***out***.println("Command from controller received: " + cmd.getType().toString());

}

});

IRobot robot = robotEnd.getRobotInterface();

//Tell the controler that the reset was completed.

robot.sendReturnReset();

}

Controller Beispiel

**public** **void** ControlerEndpointExample() **throws** InstantiationException, IllegalAccessException, IOException {

ControlerEndpoint controlerEnd = **new** ControlerEndpoint();

controlerEnd.connect(InetAddress.*getByName*("192.168.0.2"), 9999);;

controlerEnd.addOnDisconnectListener(**new** IDisconnectedEventListener() {

@Override

**public** **void** OnDisconnect() {

System.***out***.println("Controller has disconnected");

}

});

controlerEnd.addCommandListener(**new** ICommandReceiver() {

@Override

**public** **void** commandReceived(CommandBase cmd) {

System.***out***.println("Command from controller received: " + cmd.getType().toString());

}

});

IControler controler = controlerEnd.getControlerInterface();

//Reset the robot

controler.sendReset();

//Request the robot status

controler.sendGetStatus();

//Move the robot for 2 seconds(360° on both motors total)

controler.sendMoveMotor(180, 180, 360, 360);

}