Controlling Roomba:

{

"command": <commandoNummer>

"arguments": {<Your argument is invalid>}

}

“SETMOTORBRUSHVACUUM” on/off  
Arguments: { ‘MainBrush’ : 0 , ‘SideBrush’ : 0 ‘Vacuum’ : 0}  
Set main brush, side brush and vacuum. 0|1

“NEWMODE” Change Mode Roomba  
Arguments : { ‘Stop’:0 , ‘ Drive’: 0 , ‘Clean’ :0 , ‘CleanOnSpot’:0 , ‘Dock’:0 , }

2 Read state Brushes   
Return : { ‘MainBrush’ : 0 , ‘SideBrush’ : 0}  
Return state of main and side brush.

Read mode Roomba  
Arguments : { ‘Stop’:0 , ‘ Drive’: 0 , ‘Clean’ :0 , ‘CleanOnSpot’:0 , ‘Dock’:0 , }

9 Reset Roomba  
Arguments : { ‘Reset’ : 0}  
Send Roomba the Reset command.

10 Set motor speed  
Arguments : {‘Left: -100 - 100, ‘Right’: -100 – 100}  
Manual set the speed of the motors.  
  
11 Read motor speed  
Return : {‘Speed’: 0-100 }  
Read the speed of the motors.  
  
12 Read Distance driven  
Return: {‘Distance’: x , TotalDistance’: x}  
Return the distance driven since last readout  
  
13 Read Temperature  
Return: { ‘Temperature’ : x}  
Temperature in degree Celsius.  
  
14 Read Battery status  
Return: { ‘BatteryStatus’ : 0-100}  
Estimated charge of the battery. On a 0 to 100% range.  
  
15 Read bumpers  
Return {‘Middle’ : 0 ‘Left’: 0 ‘Right’: 0}

16 Read cliff  
Return { ‘Left’ : 0, ‘FrontLeft’: 0 , ‘Right’: 0 , ‘FrontRight’: 0}

18 angle  
Arguments: { ‘angle’: -180 – 180 }

19 charging state   
Arguments: {‘ charging’: 0 – 1 }

Displaylogs:  
-Read last 20 moves / logs