API

Berichten worden van en naar poort … gestuurd. Elk bericht begint met een byte die het type bericht/opdracht specificeert, gevolgd door de parameters/informatie van de opdracht/het bericht.

Nao to Goal

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| --- | --- | --- | --- |
| Name | Code | Parameters | Description |
| Error | 10000000 (0x80) |  | An error occured in the Nao, and is unable to recover. |
| Success | 10000001 (0x81) | Command | The last command with code *Command* has succeeded. |
| Failure | 10000010 (0x82) | Command | The last command with code *Command* has failed. |
| Location | 10001001 (0x89) | PlaceID | Describe the place the Nao is, in the form of an id. |
| At | 10001010 (0x8A) | MarkerID  Distance | The Nao is *Distance* rooms away from marker *MarkerId*. |
| AtObject | 10001011 (0x8B) | ObjectID | The Nao is at marker *MarkerId*. |
| Object | 10001100 (0x8C) | markerID  ObjectID | The Nao has spotted object *ObjectID* at marker *MarkerID* |
| Holding | 10001101 (0x8D) | ObjectID | The Nao is holding object *ObjectID*. |
| Agent | 10001110 (0x8E) | PlayerID | Describe the *PlayerID* of the Nao. |
| State | 10001111 (0x8F) | State | Describe the state of the Nao:  Walking  Looking  stopped |

Goal to Nao

|  |  |  |  |
| --- | --- | --- | --- |
| Name | Code | Parameters | Description |
| Exit | 00000000 (0x00) |  | Exit the program. |
| GoTo | 00000001 (0x01) | MarkerID  Distance | The Nao will go to marker *MarkerID*, stopping *Distance* rooms before the marker. |
| Pickup | 00000010 (0x02) | ObjectID | Pick up object ObjectID. If the object is in the Nao’s vision range, but the Nao can’t reach the object, it will position itself so that it can pick u het object. |
| Drop | 00000011 (0x03) |  | If the Nao is holding an object, i twill drop it. |
| Stop | 00000100 (0x04) |  | The Nao will stop all actions. |