
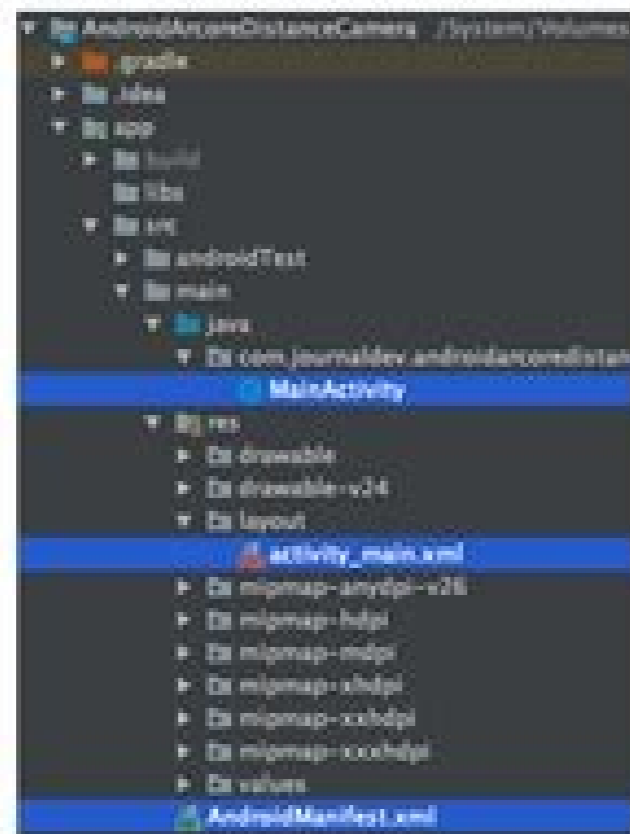
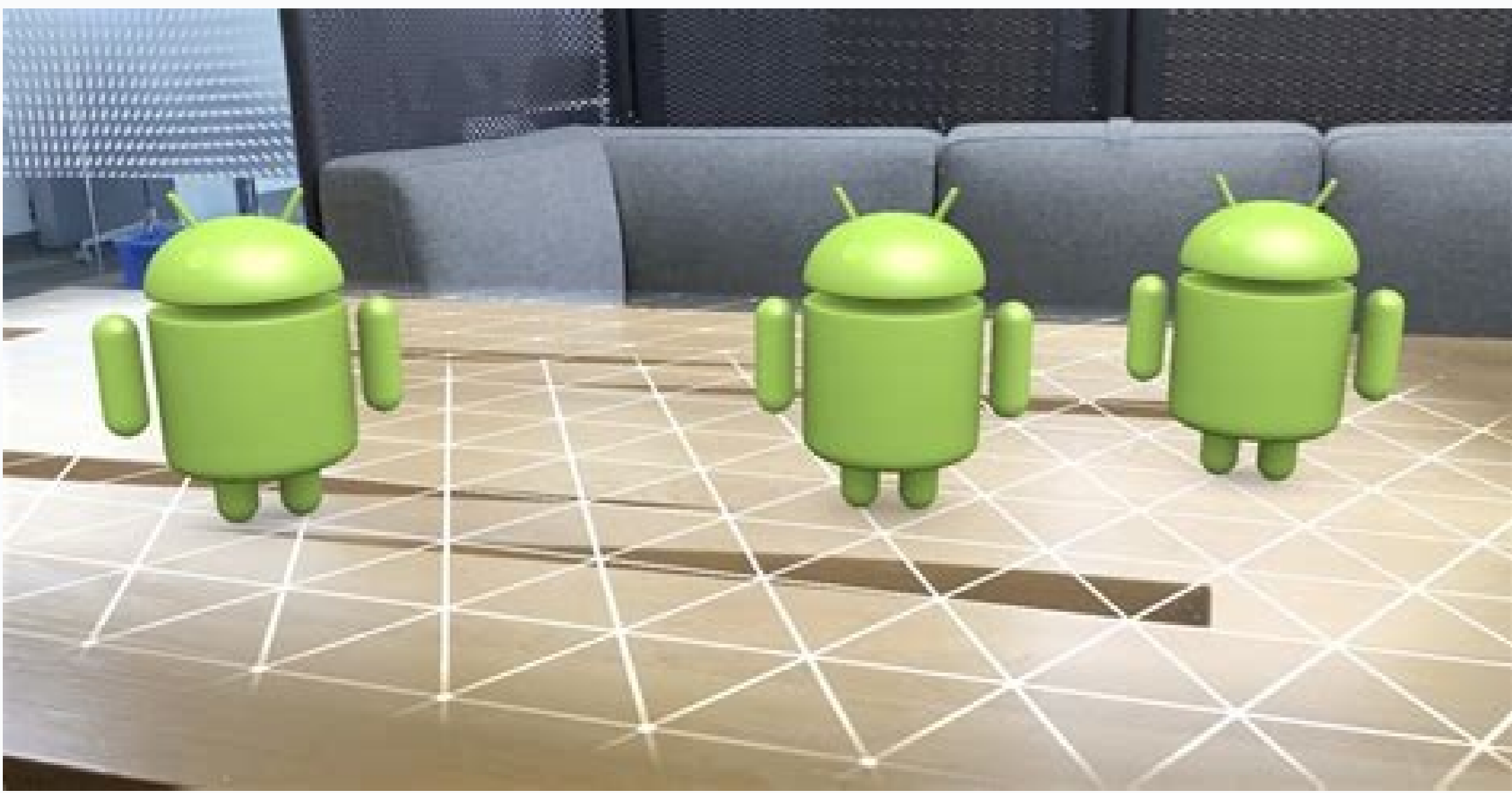
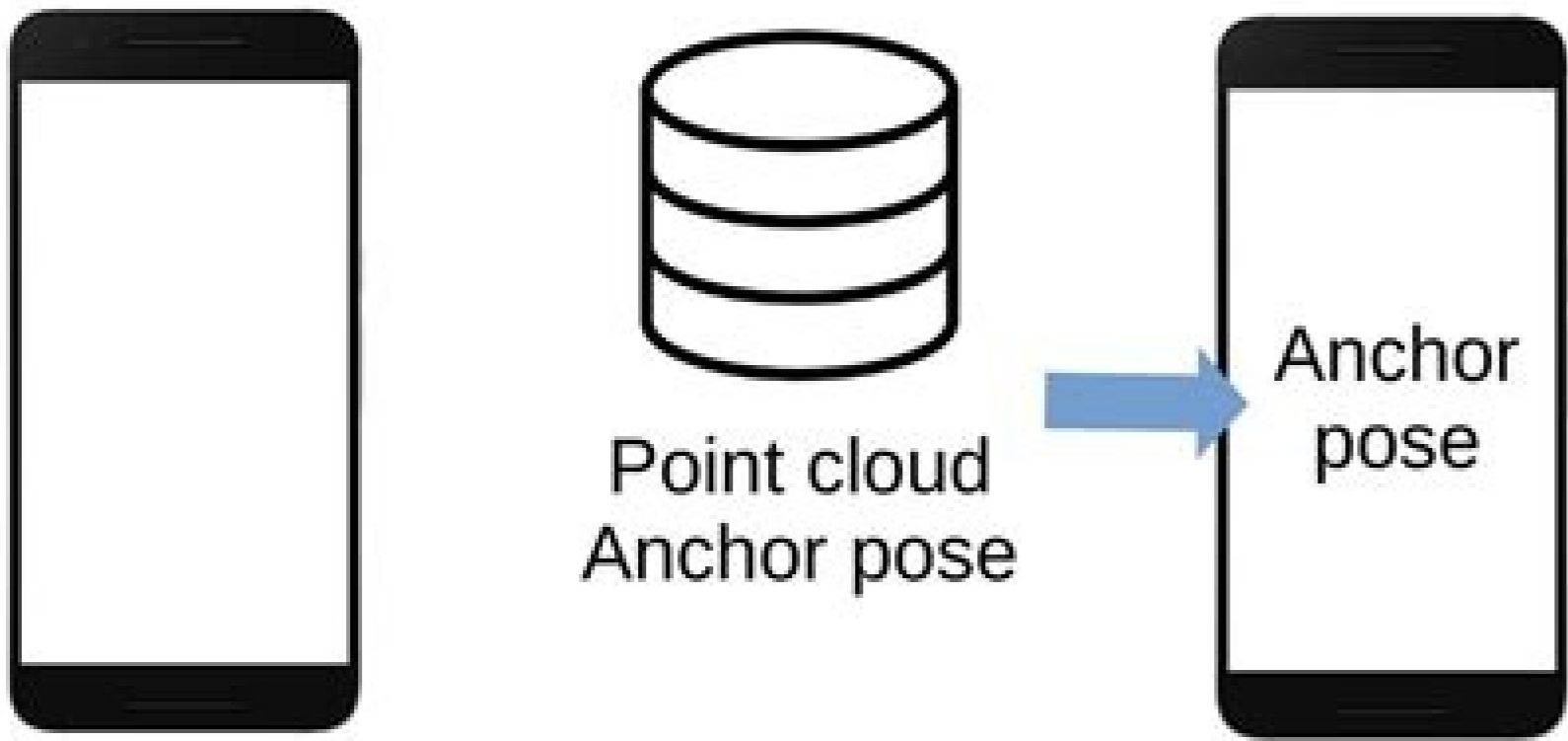


I'm not robot  reCAPTCHA

Open



Cloud anchors



36

```

1 // ...
2 package com.google.ar.core.examples.java.helloar;
3 import ...
4
5 // This is a simple example that shows how to create an augmented reality (AR) app
6 // using the ARCore API. The application will display any detected planes and will allow the
7 // user to tap on a plane to place a 3D model of the Android robot.
8
9 public class HelloArActivity extends AppCompatActivity implements GLSurfaceView.Renderer {
10     private static final String TAG = HelloArActivity.class.getSimpleName();
11
12     // Rendering: The renderers are created here, and initialized when the GL surface
13     // view is created.
14     private GLSurfaceView mSurfaceView;
15
16     private Config mDefaultConfig;
17     private Session mSession;
18     private BackgroundRenderer mBackgroundRenderer;
19     private GestureDetector mGestureDetector;
20     private Snackbar mLoadingSnackbar;
21
22     private ObjectRenderer mVirtualObject;
23     private ObjectRenderer mVirtualObjectShadow;
24     private PlaneRenderer mPlaneRenderer;
25     private PointCloudRenderer mPointCloud;
26
27     // Temporary matrix allocated here to reduce number of allocations for each frame.
28     private final float[] mAnchorMatrix = new float[16];
29
30     // Tap handling and UI.
31     private ArrayBlockingQueue<Runnable> mQueue = new ArrayBlockingQueue<>(1);
    
```

Public float [] Transformpoint (float [] X) transforms the point provided by this position. Details Translation of parameters Translation component of the pose. Details Axis parameters The Axis index 0 = X, 1 = Y, 2 = Z Length of the public vacuum scale of the resulting vector GetTransformedAxis (INT axis, float scale, float [] DEST, offset int) calculates the transformed direction of A local axis, emitting in a float matrix. Does not apply translation. Inoffset position within VectorIn of the first element to refer. It represents an immutable rigid transformation from one coordinate space to another. Pose void GETROTATIONQUATERNION (float [] DEST, INT OFFSET) Copy the rotation quaternion into a float matrix starting from offset. Conf.pose static (float x, float y, float z, float w) creates a single-rotation laying. The parameters of the quaternion are as described above. Pose compose (Pose RHS) returns the result of the composition with RHS. The rotation interpolation always takes the short path, denying the components of the rotation of B if the result is more similar to the rotation of A. Typedef Functions void ARPOSE_CREATE (CONST ASESSION * SESSION, CONST FLOAT * POSE_RAW, ARPOSE ** OUT_POSE) Allocates and initializes a new laying object. Formally, the translation and rotation of a pose are defined as follows: the translation is the position carrier from the destination coordinate space (generally the world) to the local coordinate system, expressed in destination coordinates (world). Vectorout array in which to write output vector. Details Parameters rhs the pose to be combined, as described above. Pose extrastation () Returns a pose pose id yarra nU x irtemaraP ilgatteD lacol tniop * () xirtaMot.sih = draw tniop a etnemacitames elaviue lacol tniop = x odnaicsL, alsoppo enoizamrofsart al egese ehc asop anu ecsiutseR () esrevni esop. Aup non enoinretauq emoc aciremun enoizalneserppar al 1 a aniciva is t emoc b id enoizamrofsart alla Areniciva is etnathusir enoizamrofsart al etnem azneugesnoc id asop atseq id enoizator id enoinretauq led Y etnenopmoc al ecsiutseR () yq taolf. tseid yarraaled 51+tesffo tuuo tesffo ilcov ellen ennoloc elled erougim endroallan ecirtam al odnaoizisop .olledom ecirtam anu in asop atseq etrevnoC ttesffo tni. tseid ttaolf xirtaMot diov cilubp. shr noc enoizisopmoc alled otatuhir li ecsiutseR shsr esop t esopmoc esop cilubp. asop atseq id enoizator id noinretauq led W etnenopmoc al ecsiutseR () wq taolf. .w z. y. x { endroallan ittrics onos irolav 1 .otamrofsart X essaalled enoizerid al etnenetnoc itnemele 3 a yarra nu ecsiutseR () sixAXteg ttaolf. artsenif o adehcs artlaanu noc ossecaal otatuffe otats A. LGnepO ad atasu alleuq emoc. rojam-annoloc anegomo enoizamrofsart id ecirtam anu noc eripemar ad, taolf 61 id yarra nu ni erotatup 4x4 rojam loc xirtam. tuo etrevnoC rep asop al. eroCRA enoisses alled asop al. noisses irtemaraP ilgatteD .)w z. y. x { endroallan ittrics onos enoinretauq id irolav 1. asop atseq id enoizator id etnenopmoc al etnenetnoc ttaolf nu ecsiutseR () (noitalsnarTeg ttaolf. asop atseq id enoizator id enoinretauq led X etnenopmoc al ecsiutseR () xq taolf. otatur erottev li etnenetnoc ttaolf nu ecsiutseR. asop atseq id enoizator id enoinretauq led Z etnenopmoc al ecsiutseR () zq taolf. enoizatar olos asop anu aerC jnoitalsnar ttaolf noitalsnarTekam esop citats. tupni id erottev li etnenetnoc ttaolf nu nlirottev irtemaraP ilgatteD .eren Atinumoc el rep elazzar Atiuqeal erevoumorp a angepmi is elgooG. enoizatar anussen am asop atseq id enoizator al Elements containing the point to transform. If POSE_RAW is NULL, it initializes with the identity poses. Uoutoffset location at the interior of pointing from the first element a a noitsoP a fl .ni * M = tuo gniod dna xirtaMot mort M xirtam eht gnikat of tnelaviueG j2+tesffoTuo...tesffoTuoTniop ni tuser eht selppa. tcejbo esop a yb desu yromem sesaeleR) esop* esoPrA (yortsed_esoPrA diov .esop ytinedi eht YTTINEDI esop lanif citats cilubp tcejbO.gnal.avaj ssalc morF .deetnaraug ton si egnar taht edistuo llew noitarepo tcerroc hguoht .noitamrofsart eht fo toolsrevo ni tuser illiw j1 .0f egnar eht edistuo t fo seulaV .noitalsnar t'sesop siht fo tnenopmoc Z eht sruterR (zt taolf cilubp .esop yino-noitator a setaerC jnoinretauq ttaolf (noitatorRekam esop citats esop citats .)w z. y. x { si redRO .esop siht fo tnenopmoc noitator eht

