libORS
Open Robot Simulation Toolkit

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Contents

1 Installation

The README file has more detailed installation instructions. The super quick way: on Ubuntu/Debian copy this to your console:

```
sudo apt−get install  liblapack−dev freeglut3−dev libqhull−dev libf2c2−dev
wget http: // user.cs.tu-berlin.de/              mtoussai/source-
code/libORS.10.1.tgz
tar  xvzf  libORS.10.1.tgz
cd libORS
make
cd test / ors
./ x.exe
```

2 Scope & overview

Basic tools for robot simulation. The lib defines basic data structures to describe robot configurations (trees/-graphs of rigid bodies), implements the basic computation of kinematic/Jacobian/Hessian functions, and links to many external libraries and engines for more sophisticated things. It uses:

- SWIFT++ to compute shape distances/collisions

- Featherstone's Articulated Body Dynamics as an implementation of exact dynamics on articulated tree structures (much more precise than IBDS or ODE)

- IBDS (a rather robust impuls-based physical simulator)

- ODE (I don't like it)

- OpenGL for display

- read/write of file formats for robot configurations, shape/mesh files (e.g., obj files), etc

3 Programmer's guide

Read the header
– `ors.h`

3.1 ORS data structures

- Check the Array class in `array.h` - it's yet another generic container class. There are many reasons why I decided reimplementing such a generic container (instead of using std::vector, blast, or whatever):

  – it's fully transparent, easy debugging

  – very robust range checking

  – direct linkage to LAPACK

  – tensor (multi-dimensional array) functions which are beyond most existing matrix implementations

  – etc

  Anyway, the Array class is central in all my code. To get a first impression of its usage, check the test/array. In the context of ORS, we mainly use double arrays to represent vectors, matrices and do linear algebra, note the typedef

  ```
  typedef MT::Array<double> arr;
  ```

- *Lists, Graphs, etc* In my convention a *List* is simply an array of pointers. Since arrays allow memmove operations, insertion, deletion etc are all O(1). I also represent graph structures via lists: e.g. a list of nodes and a list of edges, a node may maintain a list of adjoint edges, etc.

  For Lists (Arrays of pointers) it makes sense to have additional methods, like calling delete for all pointers, or writing the referenced objects to some output – at the bottom of `array.h` there are a number of template functions for lists and graphs.

- See the `ors.h` file. It defines a number of trivial data structures and methods that should be self-explanatory:

  – Vector

  – Matrix

  – Quaternion

  – Frame (a coordinate system)

  – Mesh (a triangulated surface)

  – Spline

- Given these types, a dynamic physical configuration is defined by lists of the following objects

  – Body: describes the physical (inertial) properties of a rigid body. This is mainly simply a Frame (position, orientation, velocities). Optionally (for dynamic physical simulation) this also includes inertial properties (mass etc) and forces.

  – Joint: desribes how two bodies are geometrically linked and what/where its degree of freedom is. The geometry of a Joint is given by a rigid transformation A (from body1 into the joint frame), a free transformation Q (the transformation of the degrees of freedom), and a rigid transformation B (from the joint frame to body2). Overall, the transformation from body1 to body2 is the concatenation $B \circ Q \circ A$.

  – Shape: describes the collision and shape properties of a rigid body. To each rigid body we may associate multiple Shapes, like primitive shapes (box, sphere, etc) or Meshes; each shape has a relative transformation from its body.

  – Proxy: describes a proximity between two shapes, i.e., when two shapes are close to each other. This includes information like the closest points on the two shapes and the normal. This information is computed from external libraries like SWIFT.

- The `Graph` data structure contains the lists of these objects and thereby describes the configuration of the whole physical system. It includes a number of low level routines, in particular for computing kinematics, Jacobians, dynamics etc. We don't describe these routines here – the SOC abstraction will provide a higher-level interface to such quantities which is closer to the mathematical notation of stochastic optimal control.

  Use the `ors_editor` application to define your own physical configuration (described later in the user's guide). Learning to define a configuration should also give you sufficient understanding of the Body, Joint, and Shape data structures.

4 User's guide

4.1 `ors_editor` and the ors-file format

- `ors_editor` is a very simple program that helps editing ors-files. ors-files contain the definition of a physical configuration. See the directory `test/ors_editor`, the binary program is test/ors_editor/x.exe, a symbolic link bin/ors_editor exists. It works like this:

```
> emacs test.ors &
> ./ors_editor  test.ors &
```

Then you edit the test.ors file in your standard text editor (here, emacs). Whenever you like, you press enter within the OpenGL window to update the display – when you made mistakes in the syntax, error messages will be output to the console.

- The general syntax of the ors-file is very simple: it lists elements in the syntax

```
elem_type elem_name (list of parents) {  attribute   list  }
```

(This is a general hypergraph syntax, which I also use in other contexts (factor graphs), where elements may connect an arbitrary number of parent elements; nodes are special case in that they connect no parents, edges are special case in that they connect exactly two parents, etc)

In our case we have three possible types: body, joint, shape. This is a simple example:

```
#any comment after a # sign

body torso (){
    X=<t(0 0 1)>              #coordinate system of this  body
}
body arm {}

shape some_shape_name (torso) {
    rel=<d(90 0 1 0)>         #rel. transf. torso −> shape
    type=3
    mesh='filename.tri'
}

joint  some_joint_name (torso arm){
    A=<t(0 0 .5) d(90 0 1 0)> #rel. transf. torso −> joint
    B=<t(0 0 .5)>             #rel. transf. joint −> arm
}
```

The attribute list is simply a list of tag=something declarations. The 'something' can be a single double number, an array [1 2 3 4] of numbers, a string in quotes, a transformation $< \cdots >$, or a list of strings in parenthesis (string1 string2 etc). Generally, you can set any attributes you like. But only some special tags have effects right now – the most important ones are explained in the example. See the routines `ors::Body::read, ors::Joint::read, ors::Shape::read` for details on which attributes have actually effects. The routine `ors::Graph::read` parses a whole ors-file and creates the respective data structures.

- We need to explain coordinate systems and how to specify transformations. A transformation is given as a sequence of primitive transformations enclosed in brackets <...>. The most important primitive transformations are a translation t(x yz), $a rotation$ d(degrees axis_x axis_y $axis_z$). Concatenating them you can generate any transformation. See the `ors::Frame::read` routine to learn about all primitive transformations.

  Every body has its own coordinate system (position and rotation in world coordinates), which you can specify with X=<...>. Also every joint has its own coordinate system – we assume that the x-axis is always the rotation axis of the joint. One can specify the coordinate system of a joint directly with X=<...> (in world coordinates), or the relative transformations from parent→joint→child with A=<...> and B=<...>, respectively. Specifying all these transformation at the same time is redundant, of course. Whatever transformations you do not specify (including body coordinates), the parser tries to compute from the given absolute or relative transformations and the tree structure of the kinematics. [[This doesn't work fully automatically in the current version!]]

4.2   ors_fileConverter

To view, convert, resize, and cleanup meshfiles, there is a little application `test/ors_fileConverter/x.exe` (and a symbolic link bin/ ors_fileConverter). It simply provides an application interface to the functionalities of the `ors::Mesh` data structure. Please see the `test/ors_fileConverter/main.cpp` to learn about all functionalities. Test something like

```
> ./ ors_fileConverter  filename.obj  −view −box
> ./ ors_fileConverter  filename. stl  −view −box −center −qhull −save
```