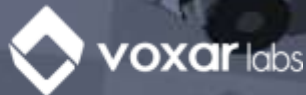


V-REP Robot Simulator as a Validation Tool for Computer Vision

Mirella Pessoa de Melo, Lucas Maggi, Rafael Roberto, João Marcelo Teixeira, Veronica Teichrieb {*mspm, lom, rar3, jmxnt, vt*}@cin.ufpe.br



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Summary

- Theoretical background
 - Computer vision
 - V-REP
- Practice
 - Creating scene in V-REP (elements)
 - Integrating V-REP and OpenCV with Visual Studio
 - Access the kinect image through API
 - Line follower robot
 - Controlling Pioneer Robot through keyboard

Computer vision: what's that?!

- “Just like to hear is not the same as to listen, to take pictures is not the same as to see and by seeing, we really mean understanding”, Stanford AI Lab's Dr. Fei-Fei Li.
- Teach machine to visually understand the world like a human.

Computer vision:: applications

- Face recognition



Computer vision:: applications

- Self-driving cars



Computer vision:: applications

- Self-driving cars



Computer vision:: applications

- Security



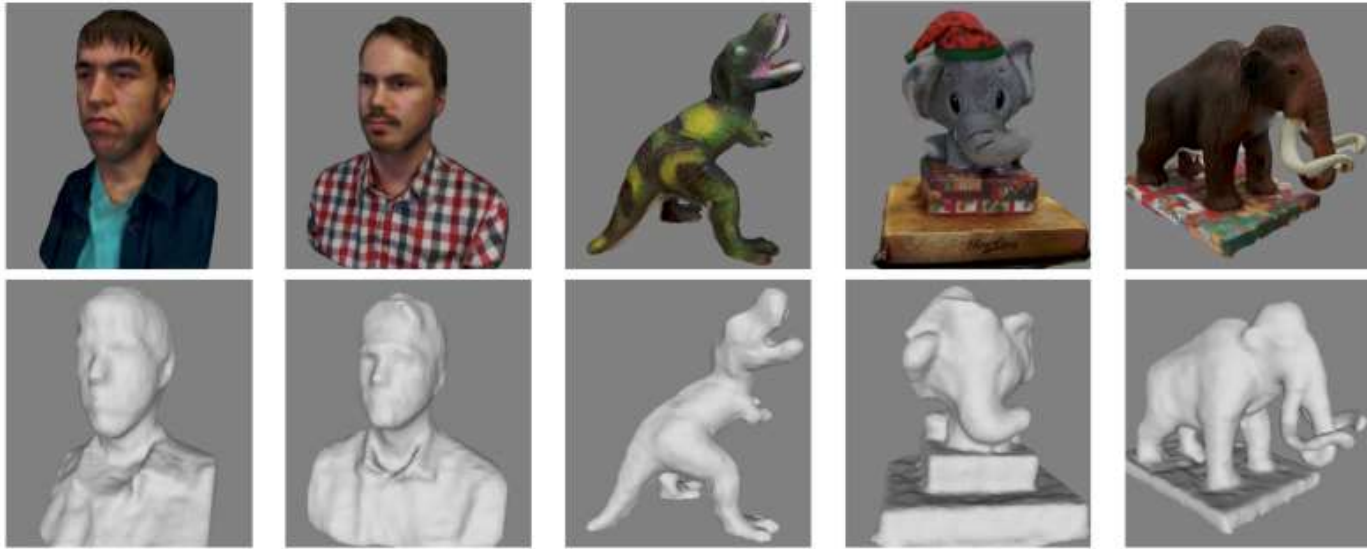
Contextualizing:: applications

- Tracking



Computer vision:: applications

- 3D reconstruction

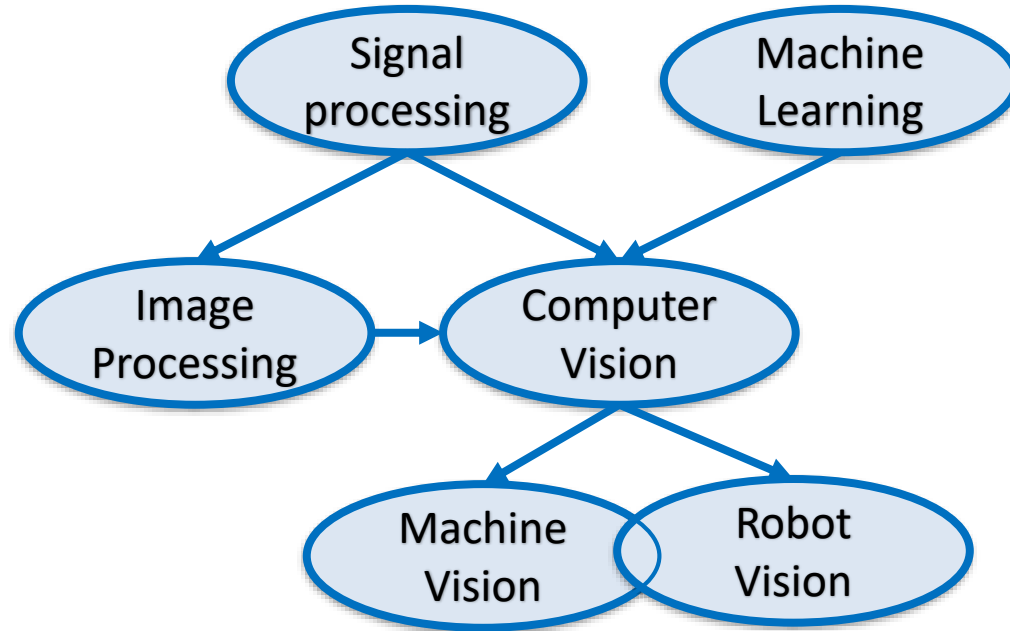


Computer vision:: applications

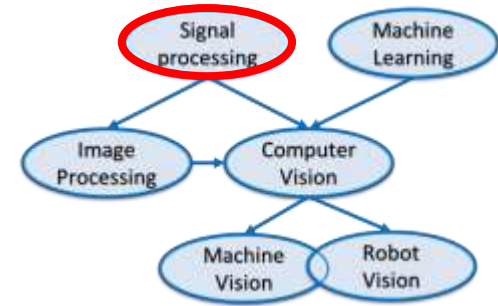
- 3D reconstruction



Contextualizing:: related areas

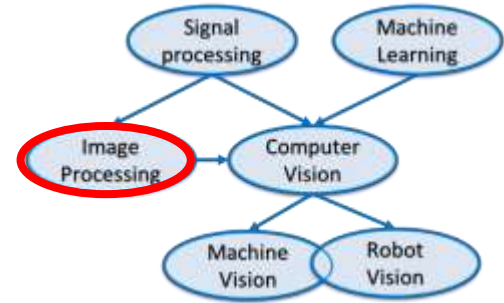


Contextualizing:: related areas:: signal processing



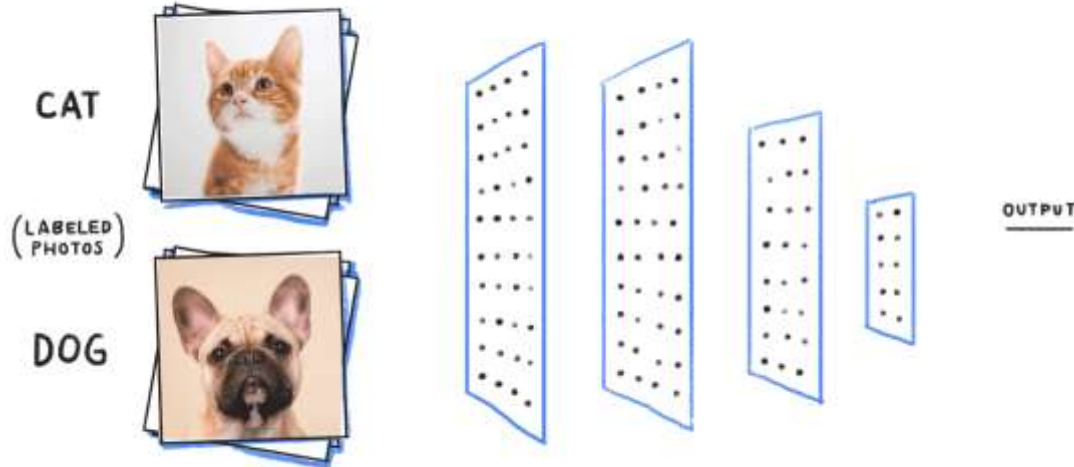
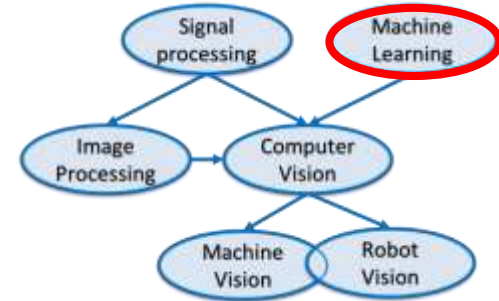
Input	Output
Electrical signals	Electrical signals

Contextualizing:: related areas:: image processing



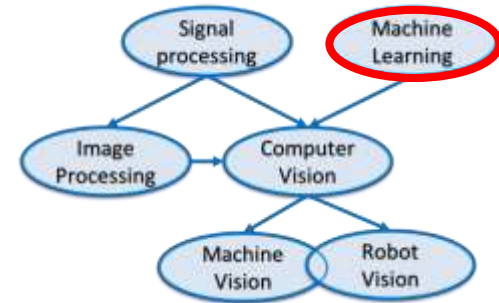
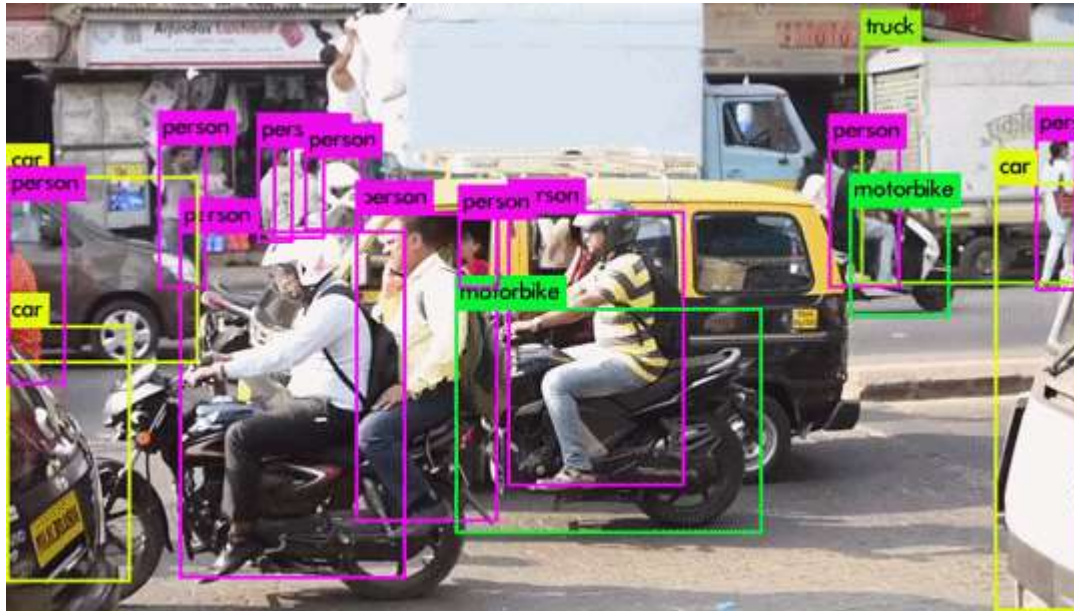
Input	Output
Image	Image

Contextualizing:: related areas:: machine learning in computer vision



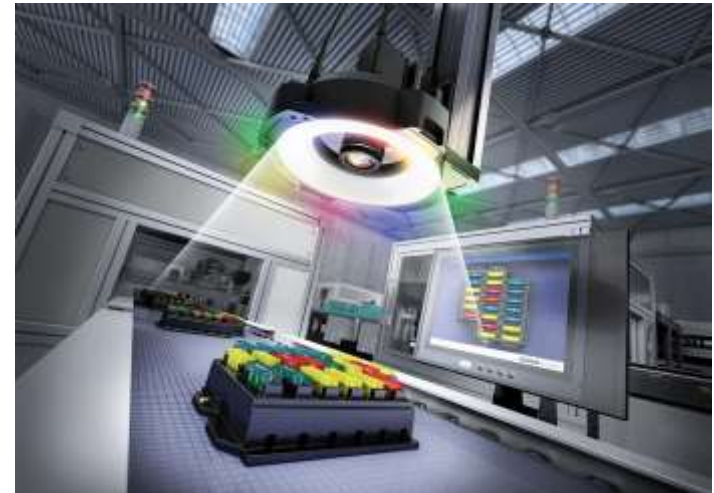
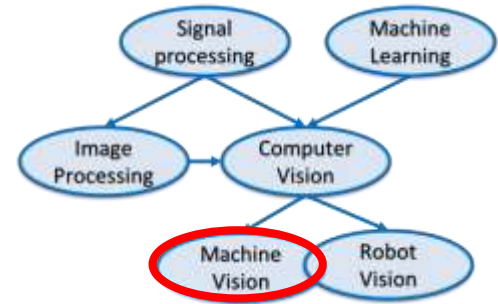
Input	Output
Images	Informations

Contextualizing:: related areas:: machine learning in computer vision



Contextualizing:: related areas:: machine vision

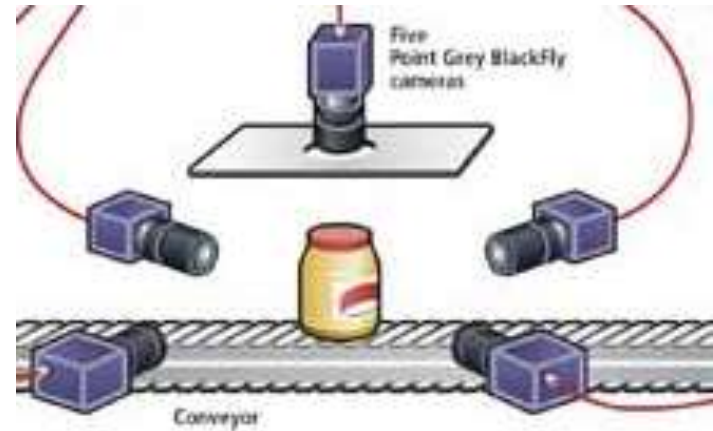
- Machine vision traditionally refers to the use of computer vision in an industrial or practical application or process;
- Computer vision applied in industry.



Input	Output
Image	Informations

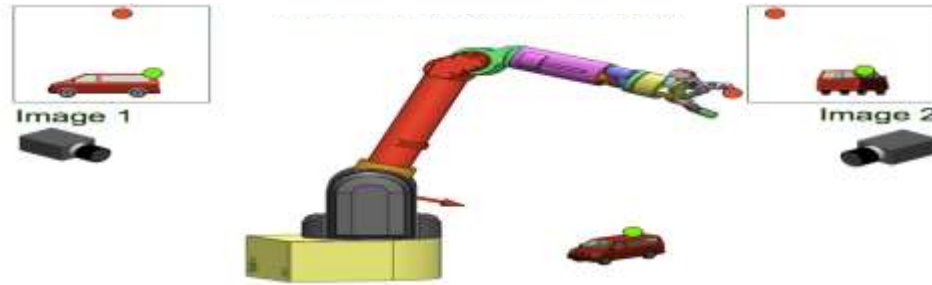
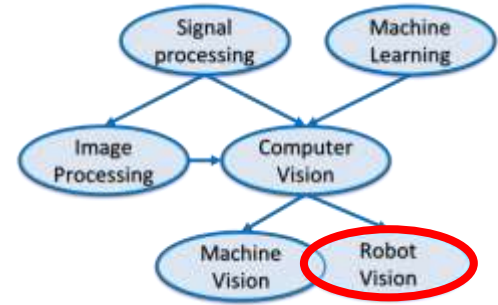
Contextualizing:: related areas:: machine vision:: applications

- Presence and absence of components
- Defects detection
- Parts identification, counting, dimensions measurement and positioning
- Quality of barcode grading print
- Color identification



Contextualizing:: related areas:: robot vision

- Robot Vision must incorporate aspects of robotics into Computer Vision techniques and algorithms, such as kinematics



Input	Output
Image	Physical actions

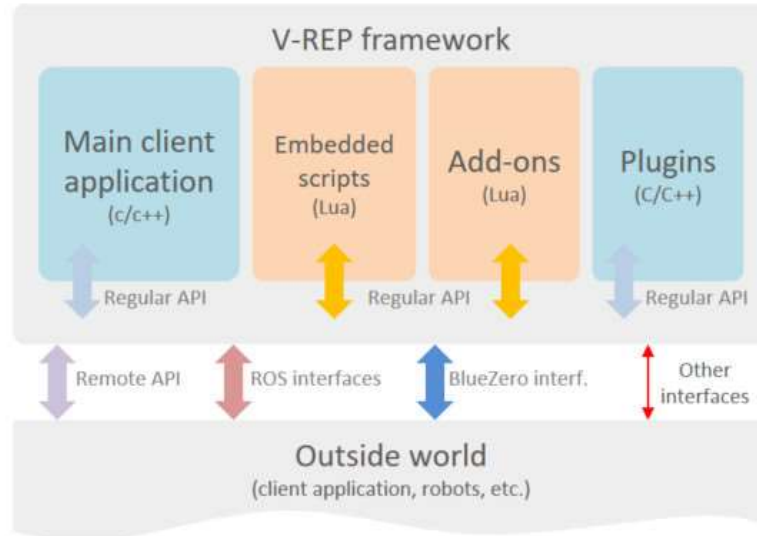
V-REP: what's that?!



Create. Compose. Simulate. **Any Robot.**

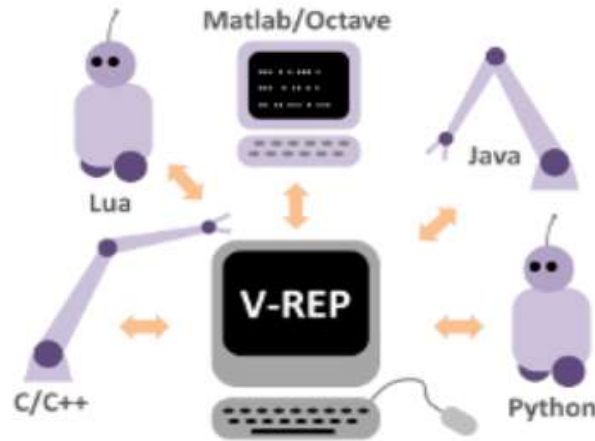
V-REP: what's that?!

- Each element can be individually controlled by an embedded script, a plugin, ROS nodes, BlueZero nodes or remote API clients.



V-REP: what's that?!

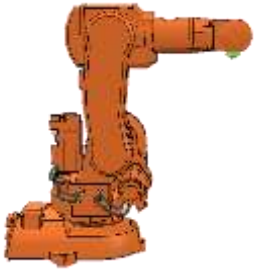
- Controllers can be written in C/C++, Python, Java, Lua, Matlab or Octave.



V-REP: it's a good idea?!

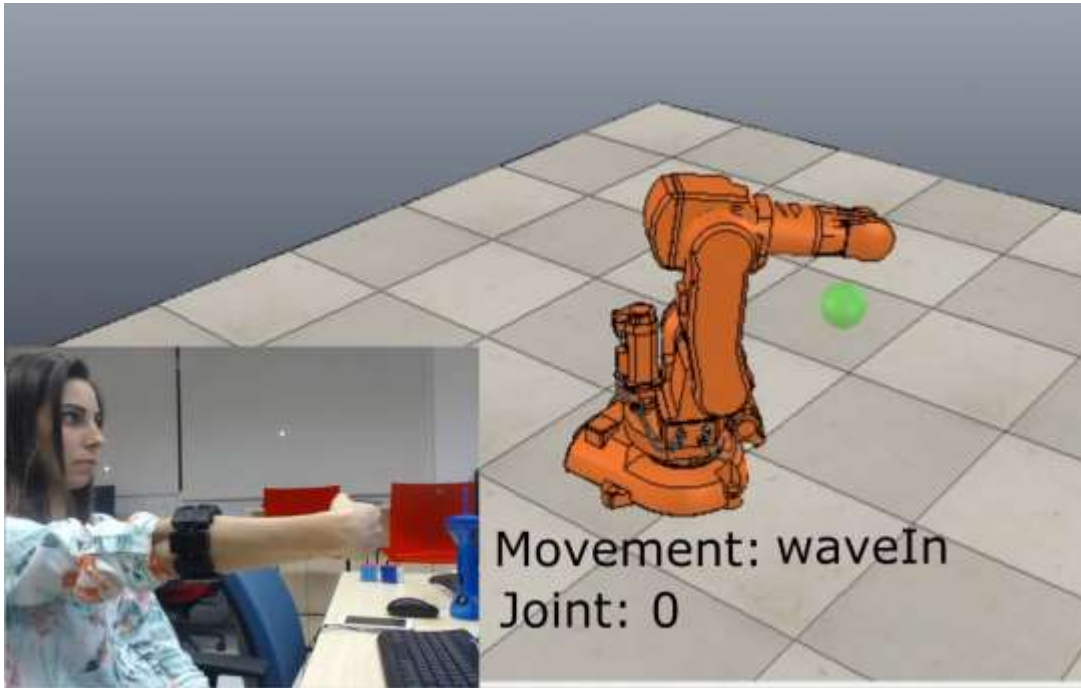


- Virtual simulators represent a simple and inexpensive alternative to create systems, platforms and prototypes;

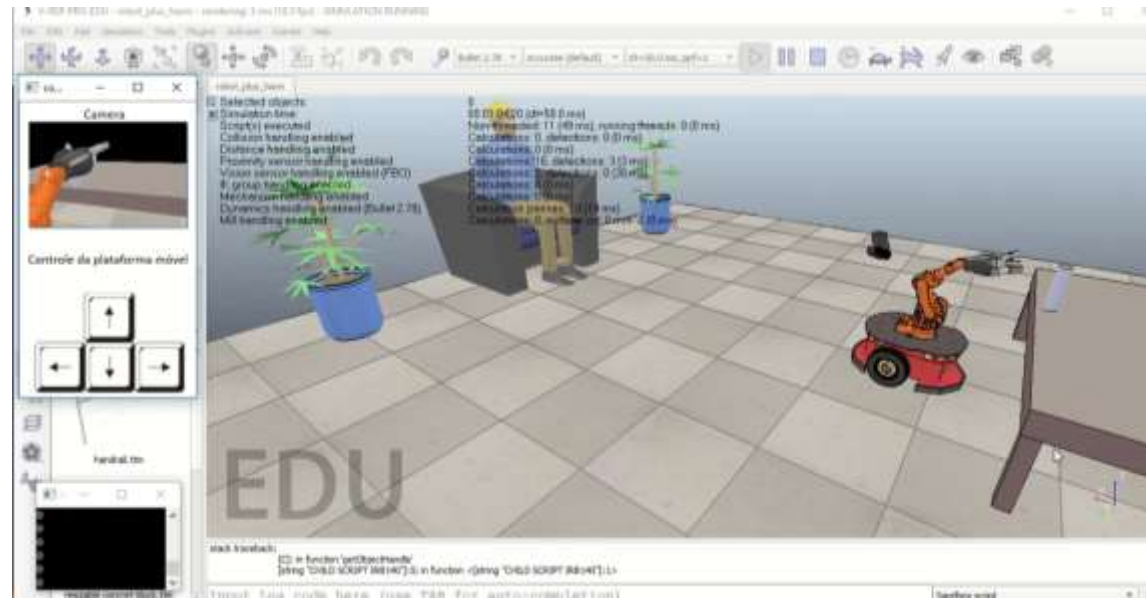


- Besides creating, it's possible to simulate and then, validate (or not) the idea;
- Avoid problems and possible mistakes during the real implementation (isolate variables).

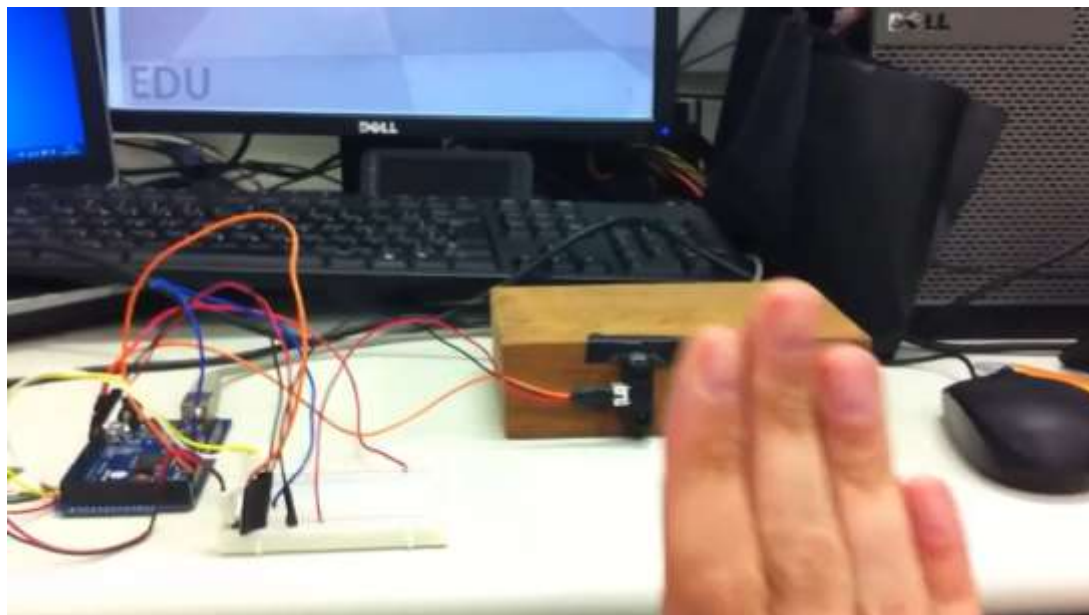
V-REP:: applications



V-REP:: applications



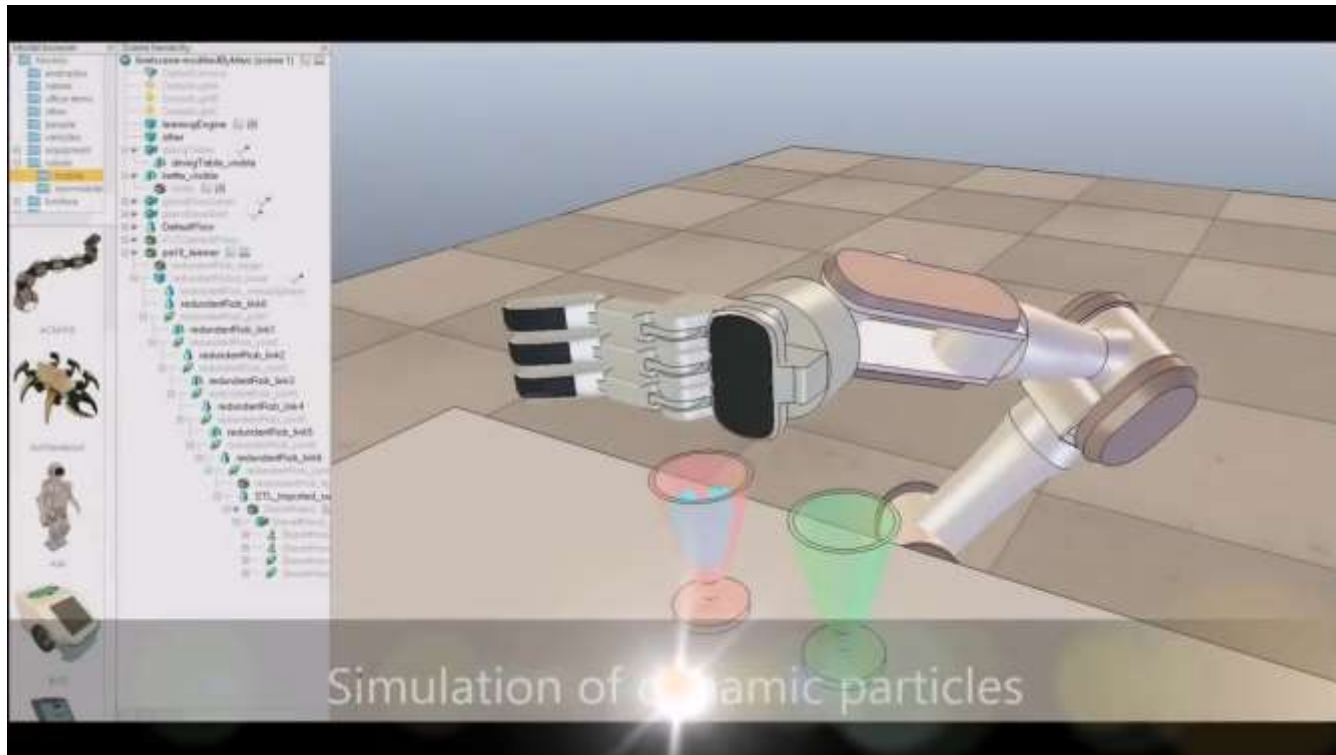
V-REP:: applications



V-REP:: applications



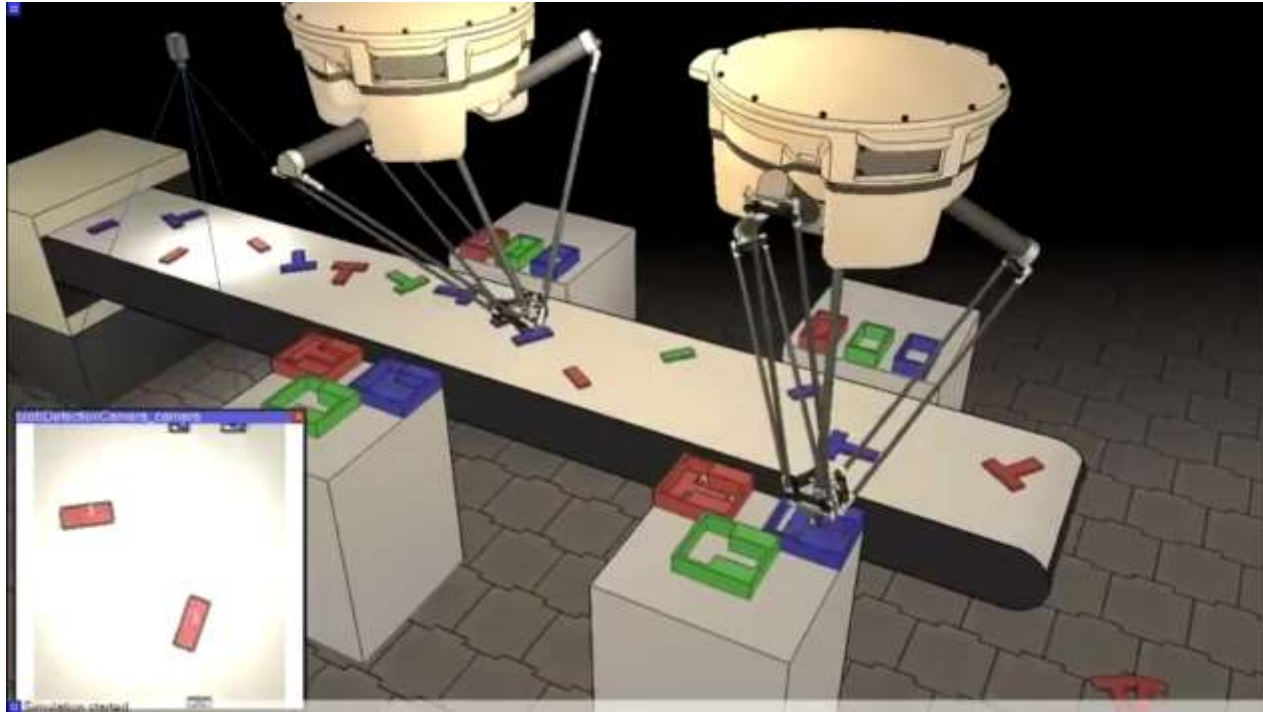
V-REP:: applications



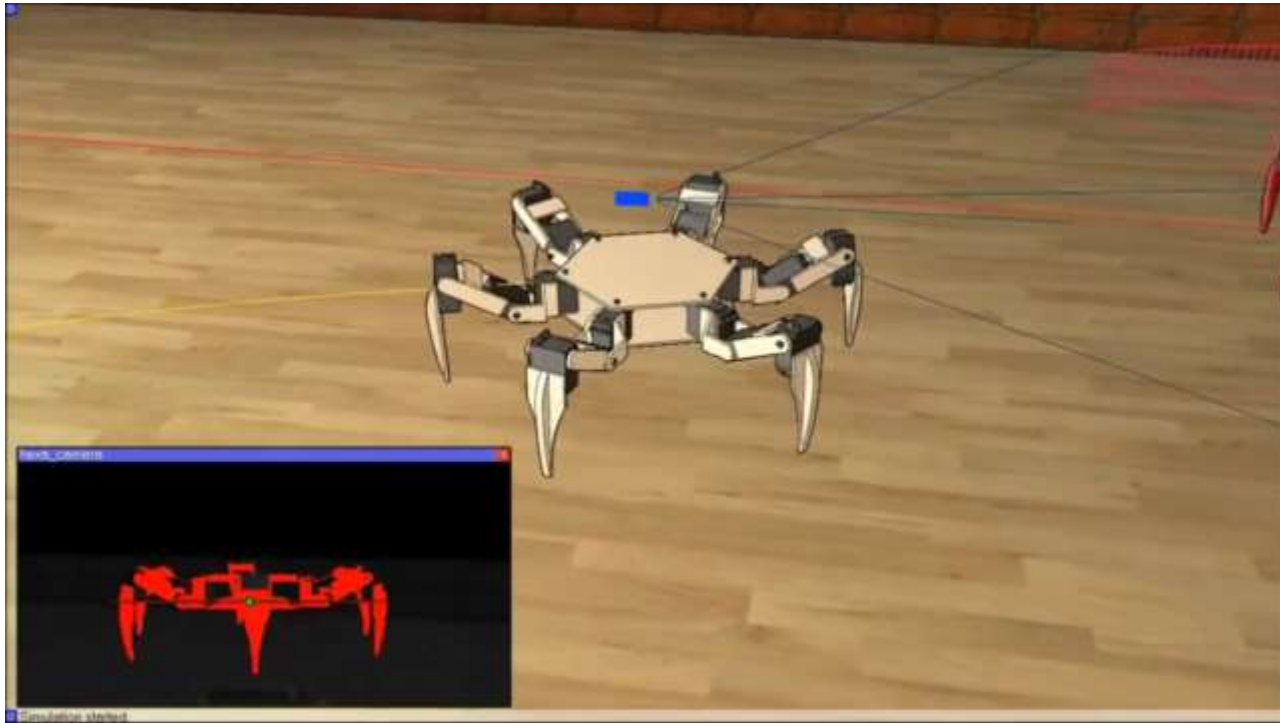
V-REP:: applications



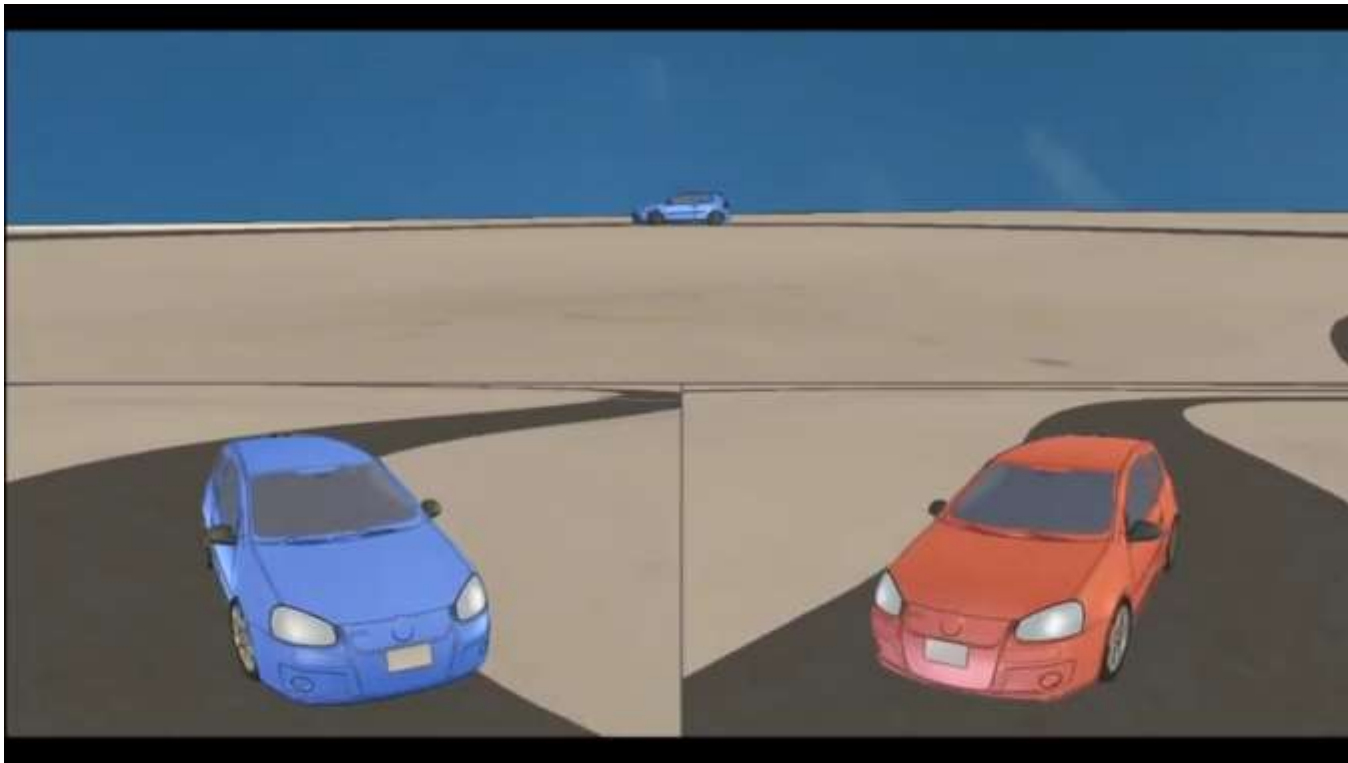
V-REP:: applications with computer vision



V-REP:: applications with computer vision



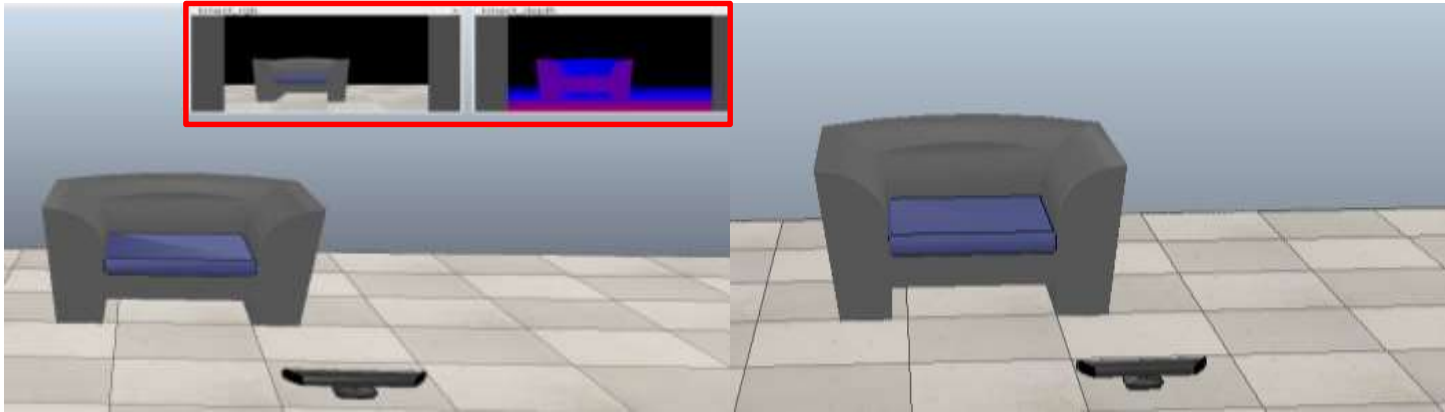
V-REP:: applications with (no) computer vision



V-REP:: vision sensor and camera

Vision sensor

Camera



V-REP:: vision sensor and camera

Vision sensor	Camera
Fixed resolution	No specific resolution (adjust automatically)
Can be accessed via API	Not directly available via the API, but via a callback mechanism
Processing filters are available	Image processing not directly supported
Can only display renderable objects	A camera can display all object types

V-REP:: vision sensor:: renderable objects



Shapes



Paths



Mirrors



Octrees

V-REP:: vision sensor:: renderable objects



Shapes: rigid mesh objects composed of triangular faces.



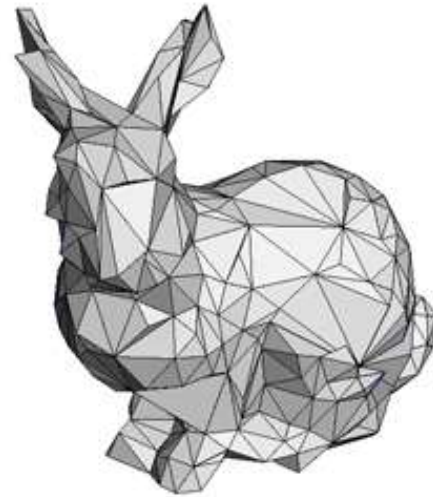
Paths



Mirrors



Octrees



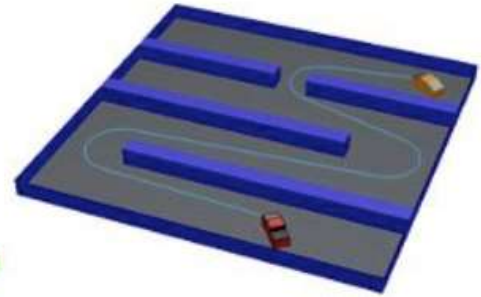
V-REP:: vision sensor:: renderable objects

 Shapes

 Paths: an object that defines a path or trajectory in space.

 Mirrors

 Octrees



V-REP:: vision sensor:: renderable objects



Shapes



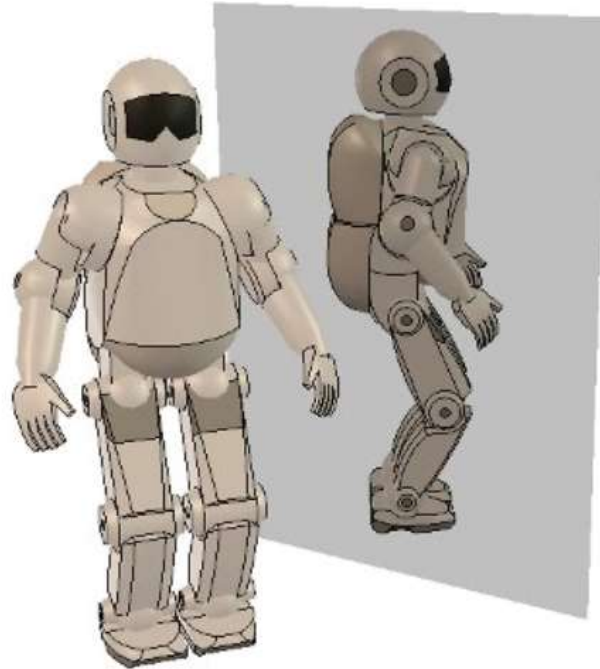
Paths



Mirrors



Octrees



V-REP:: vision sensor:: renderable objects



Shapes



Paths

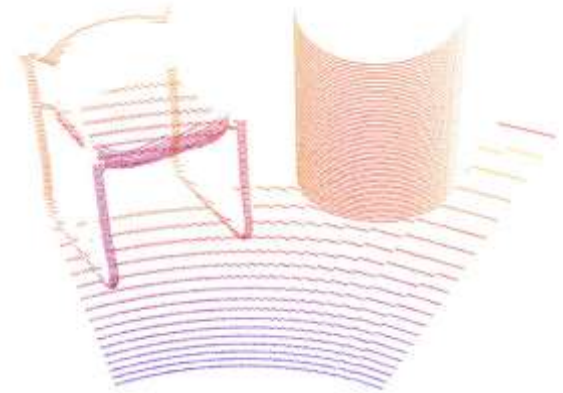
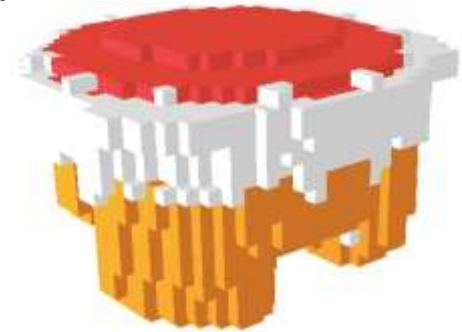


Mirrors



Octrees

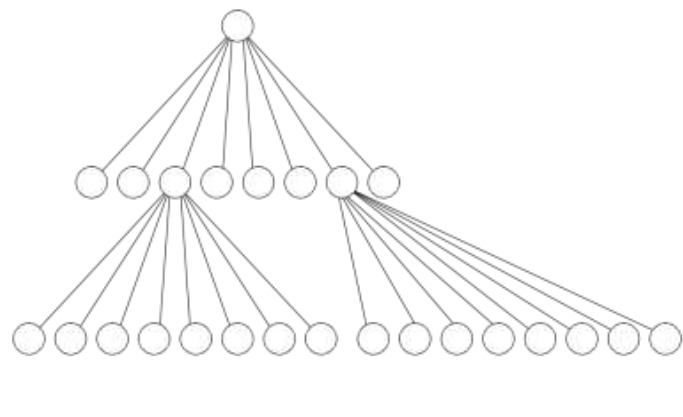
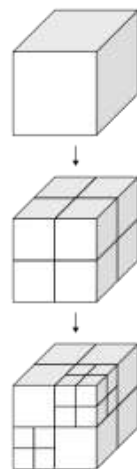
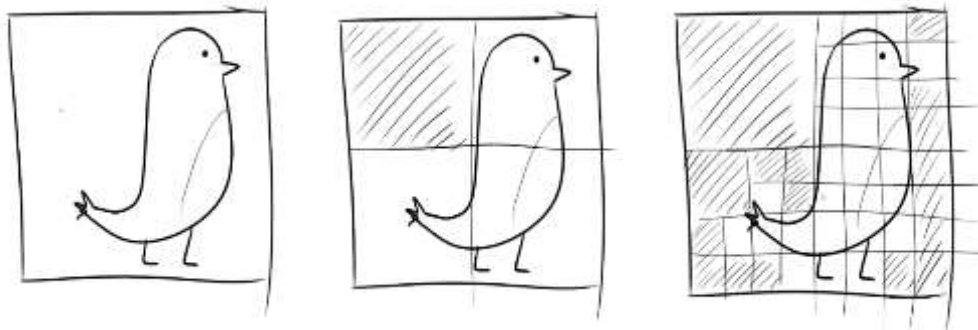
- voxels
- points cloud



V-REP:: vision sensor:: renderable objects



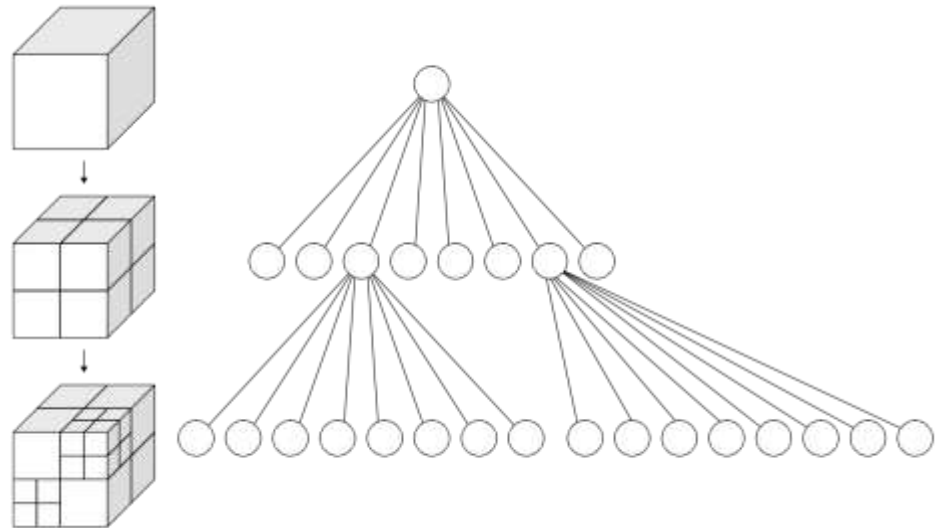
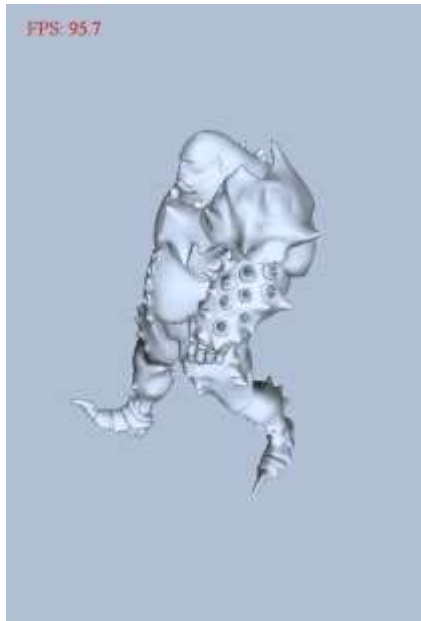
Octrees



V-REP:: vision sensor:: renderable objects



Octrees

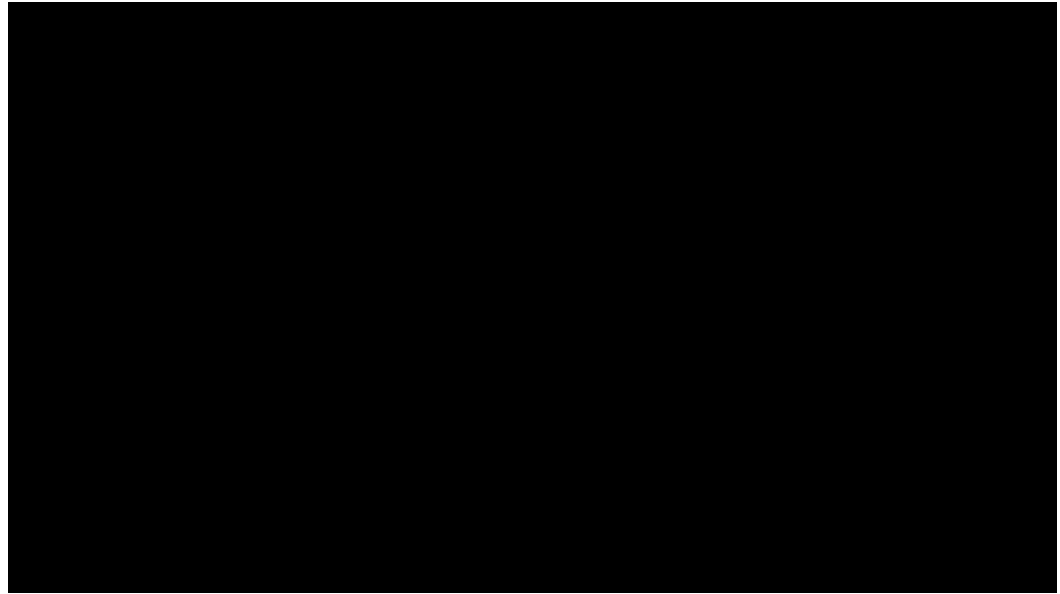


V-REP:: vision sensor:: renderable objects



Octrees made
by voxels

- Collidable
- Measurable
- Detectable objects

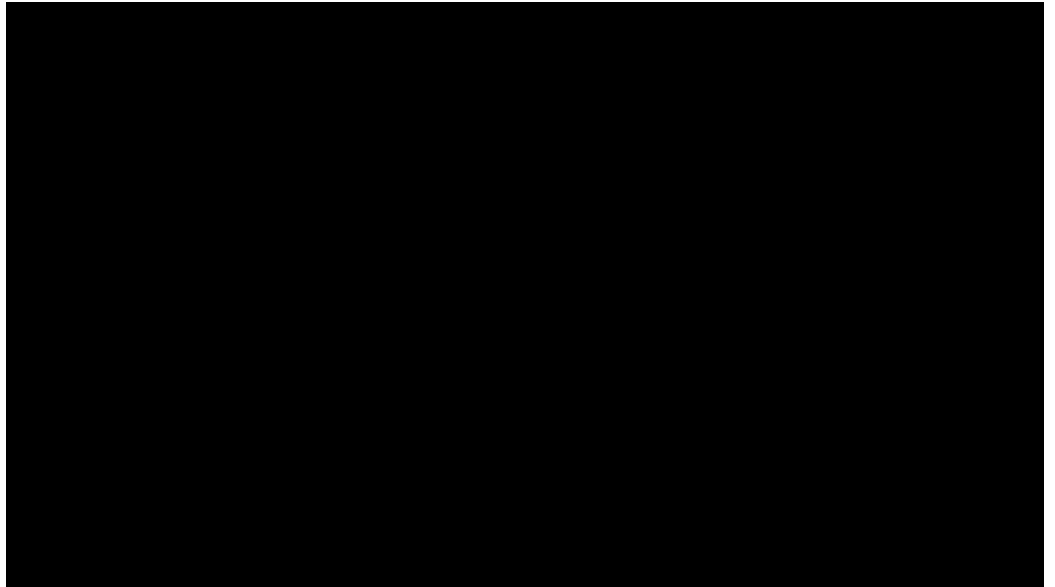


V-REP:: vision sensor:: renderable objects



Octrees made
by points

- Collidable
- Measurable
- Detectable objects



V-REP:: vision sensor:: graphs



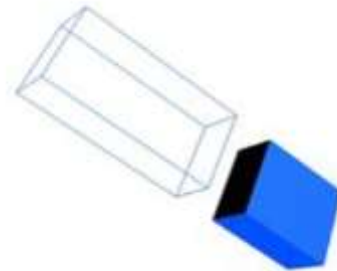
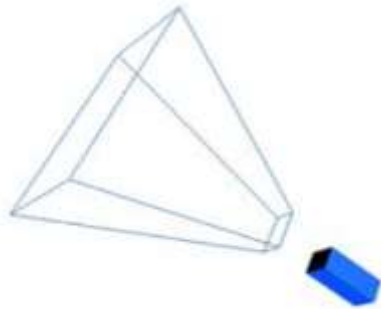
OBS: data streams recorded by a graph can be exported to a *.csv file.

Data related to vision sensors:

- Minimum red/green/blue/intensity/depth value
- Maximum red/green/blue/intensity/depth value
- Average red/green/blue/intensity/depth value
- Detection state (detect or not something)

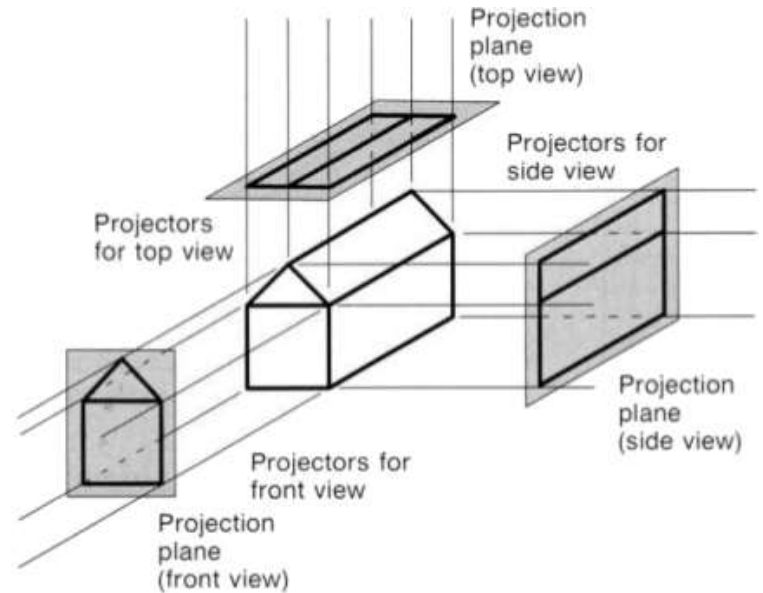
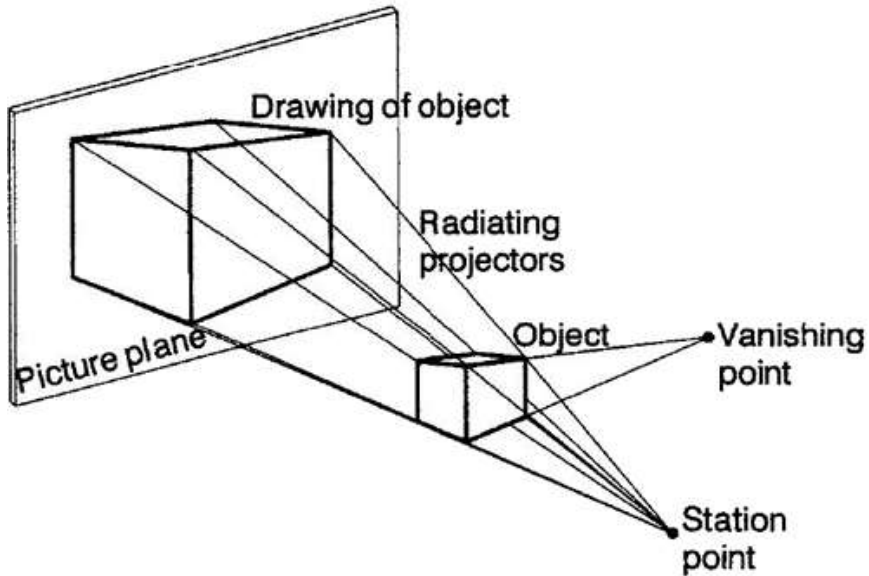
V-REP:: vision sensor:: types

- Perspective projection
- Ortographic projection



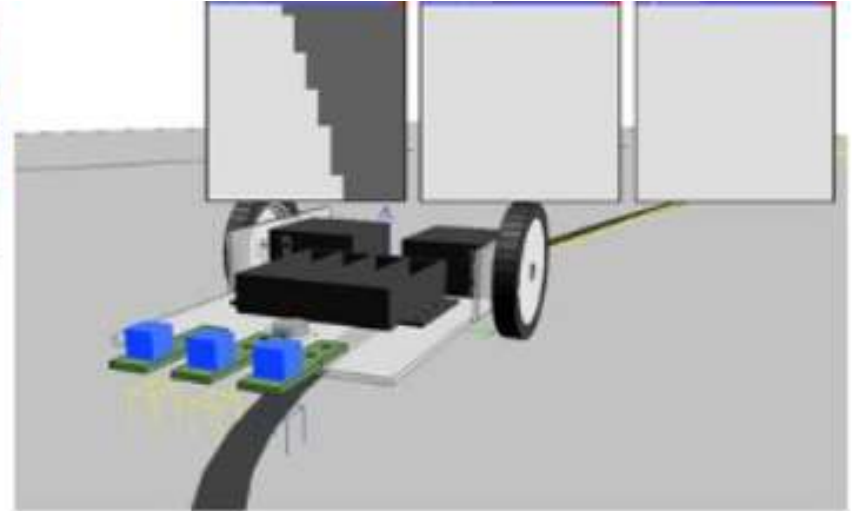
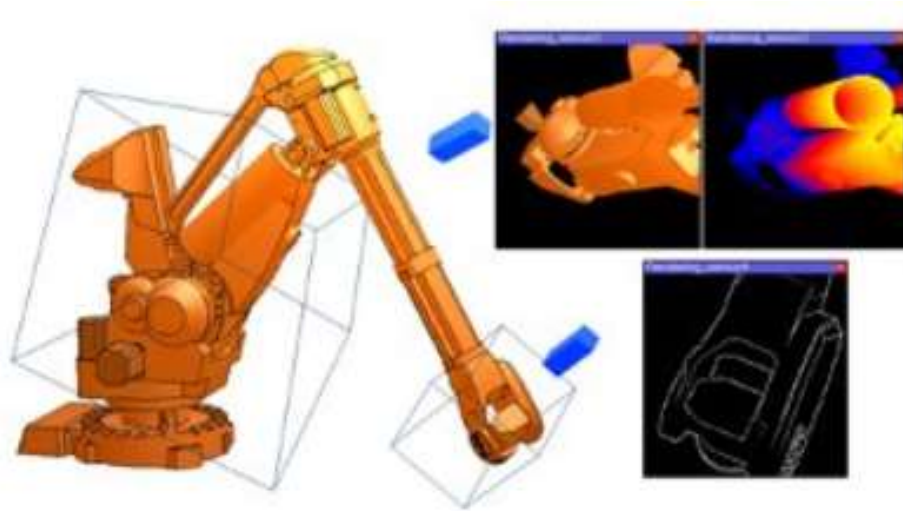
V-REP:: vision sensor:: types

- Perspective projection
- Orthographic projection

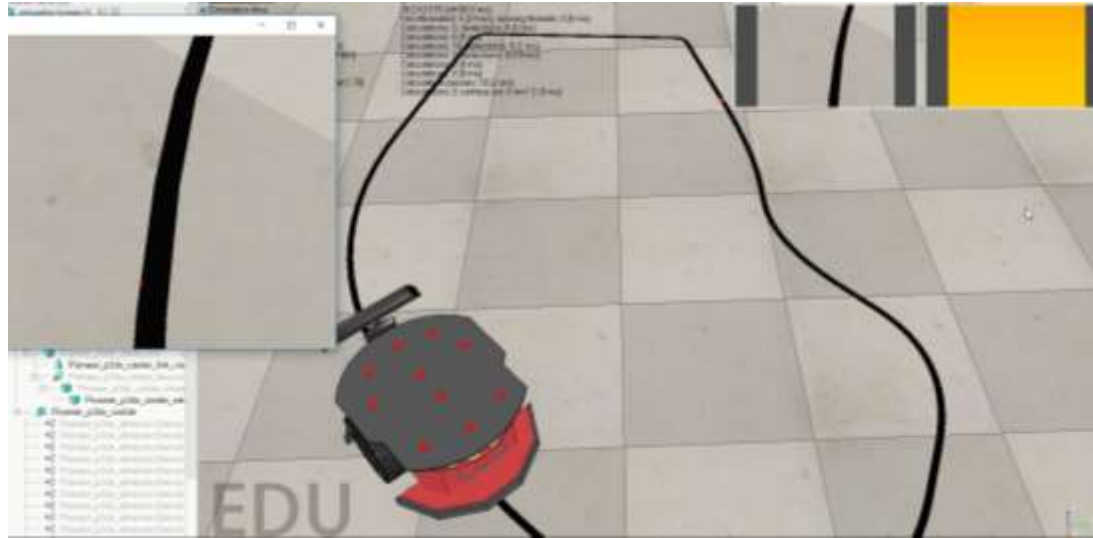


V-REP:: vision sensor:: types

- Perspective projection
- Ortographic projection



MORE ABOUT V-REP DURING PRATICAL PART!!!

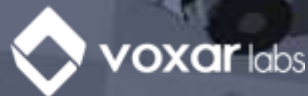


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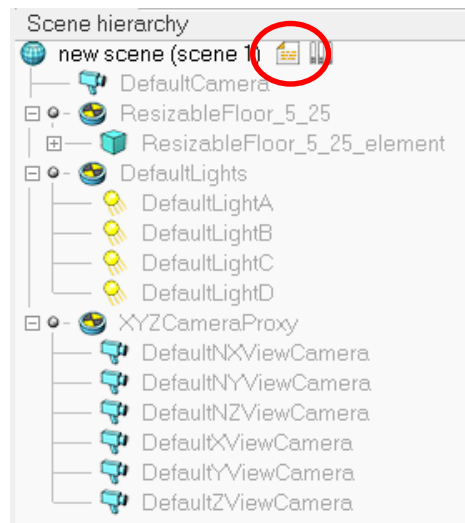
Summary

- Theoretical background
 - Computer vision
 - V-REP
- Practice
 - Creating scene in V-REP
 - Integrating V-REP and OpenCV with Visual Studio
 - Access the kinect image through API
 - Line follower robot
 - Controlling Pioneer Robot through keyboard

Before going to V-REP...

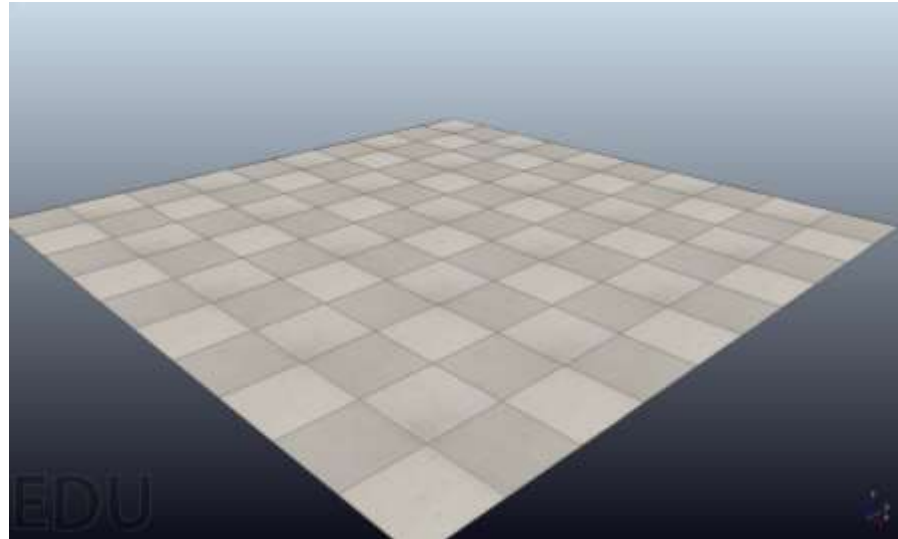
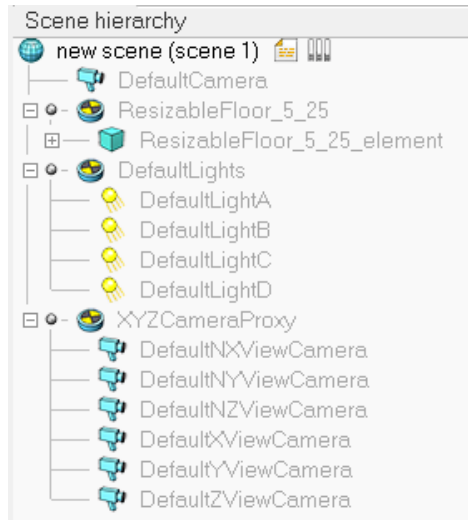
V-REP:: scenes

- The environment
- The main script
- Pages and views



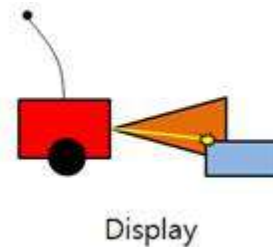
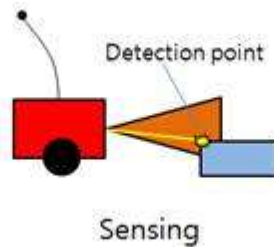
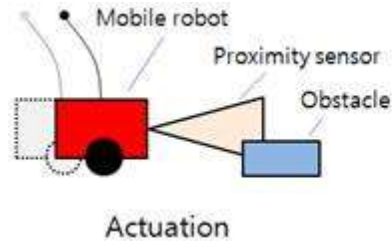
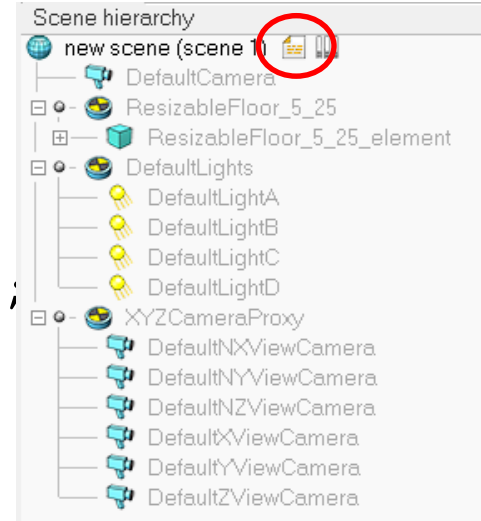
V-REP:: scenes:: the environment

- The environment is composed by properties as ambient light, background color, etc.



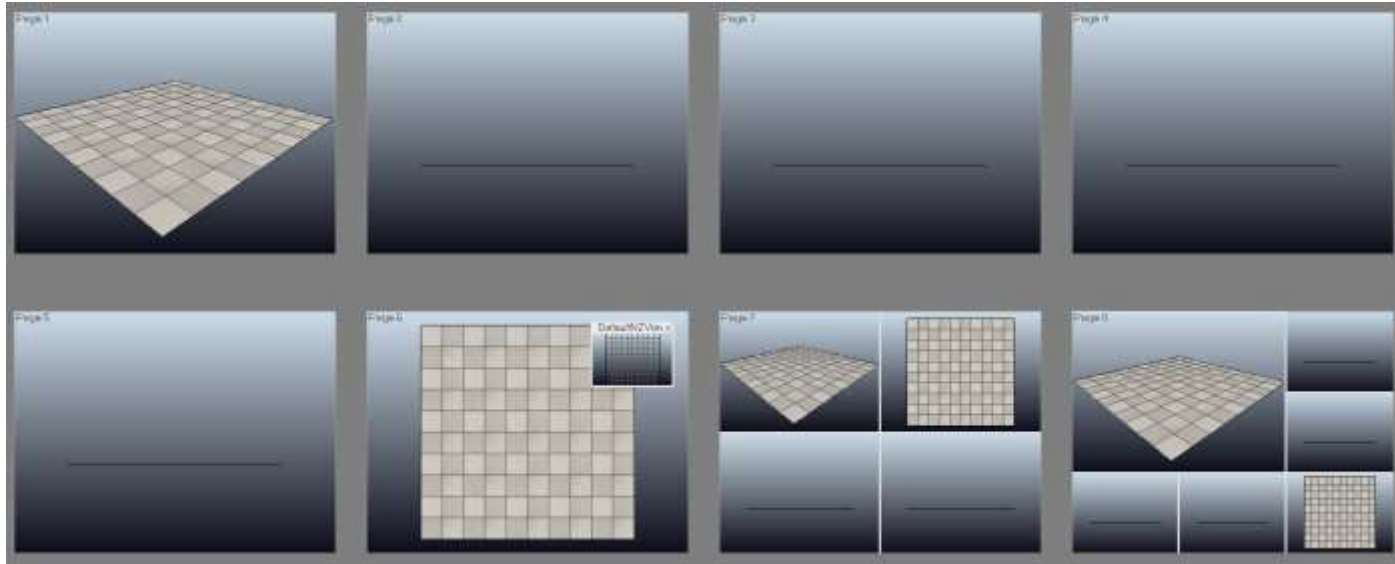
V-REP:: scenes:: main script

- The main script
 - the initialization function: `sysCall_init;`
 - the actuation function: `sysCall_actuation;`
 - the sensing function: `sysCall_sensing;`
 - the restoration function: `sysCall_cleanup.`



V-REP:: scenes:: pages and views

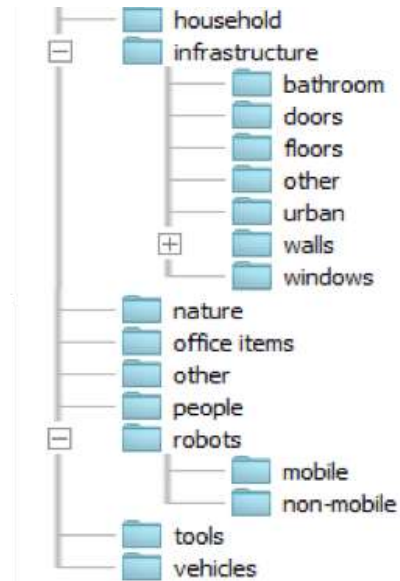
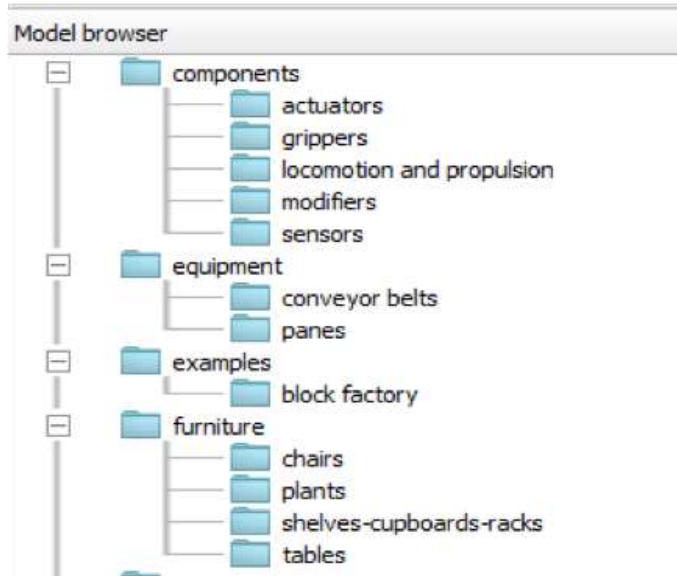
- Pages and views



Going to V-REP...

Exploring V-REP

- Exploring a little bit



Exploring V-REP

- Exploring a little bit
 - Drag the Pioneer Robot to the scene and... (robots/mobile)



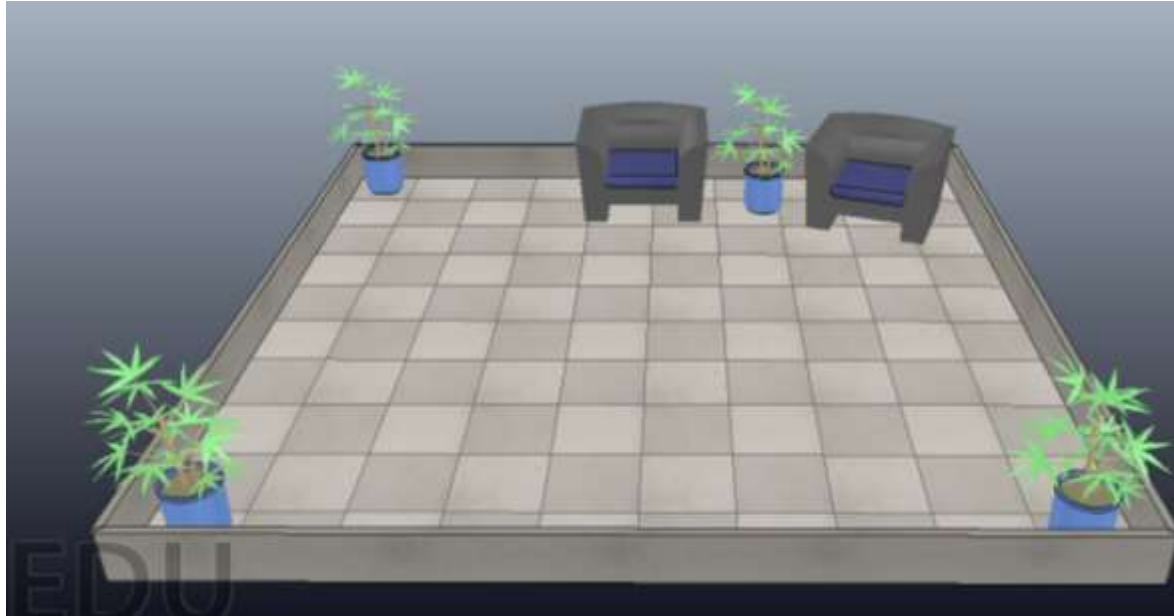
Practice 1: creating scene in V-REP

- Infrastructure/other/resizable concret block



Practice 1: creating scene in V-REP

- Furniture/chairs - plants



Practice 1: creating scene in V-REP

- Robots/mobile



Practice 1: creating scene in V-REP



Practice 2: accessing the image through API

1°) integrate kinect to the scene and associate it with Pioneer

2°) configure Visual Studio with OpenCV and V-REP API

3°) access kinect image by external API

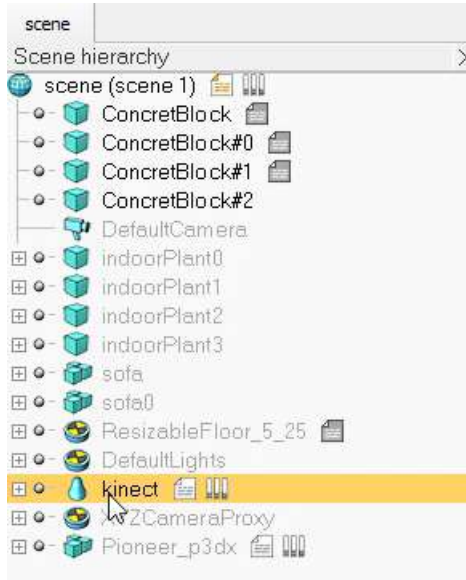
Practice 2: accessing the image through API

- Components/sensors/kinect



Practice 2: accessing the image through API

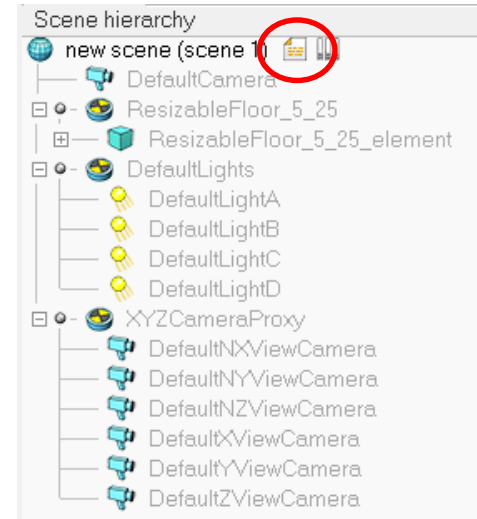
- Associate the kinect with Pioneer



Practice 2: accessing the image through API

- Embedded script – main script

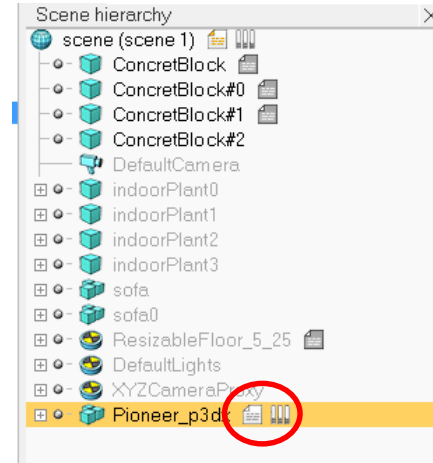
```
11 function sysCall_init()  
12     sim.handleSimulationStart()  
13     sim.openModule(sim.handle_all)  
14     sim.handleGraph(sim.handle_all_except_explicit,0)  
15     simRemoteApi(19997)  
16  
17 end  
18
```



Practice 2: accessing the image through API

- Embedded script – pioneer robot

```
function sysCall_init()  
    motorLeft=sim.getObjectHandle("Pioneer_p3dx_leftMotor")  
    motorRight=sim.getObjectHandle("Pioneer_p3dx_rightMotor")  
    vLeft =0;  
    vRight=0;  
    sim.setJointTargetVelocity(motorLeft,vLeft)  
    sim.setJointTargetVelocity(motorRight,vRight)  
end
```



Practice 2: accessing the image through API

- Going to Visual Studio

File Edit View Project Debug Team Tools Test Analyze Window Help

- New
- Open
- Start Page
- Close
- Close Solution
- Save Selected Items (Ctrl+S)
- Save Selected Items As...
- Save All (Ctrl+Shift+S)
- Page Setup...
- Print... (Ctrl+P)
- Account Settings...
- Recent Files
- Recent Projects and Solutions
- Exit (Alt+F4)

Project... (Ctrl+Shift+N)
Repository...
File... (Ctrl+N)
Project From Existing Code...

Recent

Today

v-rep_atividades.sln
C:\Users\Joma\Desktop\graficas_mini_cursor\v-rep_atividades

This month

Open

Get code from a remote version control system or open something on your local drive.

- Checkout from:
- Visual Studio Team Services
 - Open Project / Solution
 - Open Folder
 - Open Website

New project

Search project templates

Recent project templates:

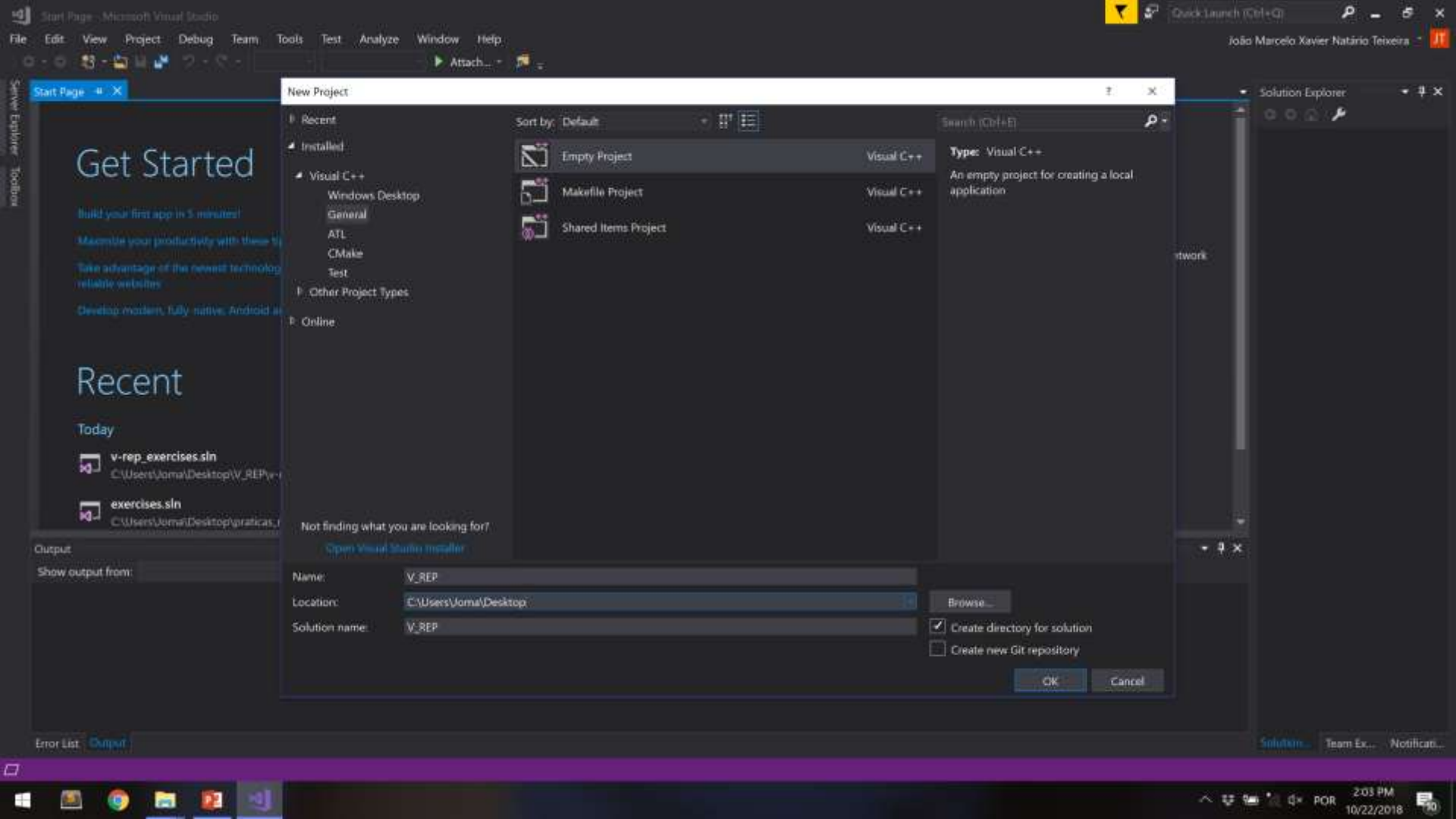
- Empty Project (C++)

Developer News

We are unable to download content due to network issues.
[Click to retry](#)

Error List | Search Error List

Errors Warnings Messages



Start Page

Get Started

Build your first app in 5 minutes!

Maximize your productivity with these tips!

Take advantage of the newest technology with these reliable websites!

Develop modern, fully native, Android apps!

Recent

Today

- v-rep_exercises.sln
C:\Users\Joma\Desktop\V_REP\...
- exercises.sln
C:\Users\Joma\Desktop\graticas\...

New Project

Sort by: Default

- Recent
- Installed
 - Windows Desktop
 - General
 - ATL
 - CMake
 - Test
 - Other Project Types
 - Online

Search (Ctrl+F)

Type: Visual C++
An empty project for creating a local application

	Empty Project	Visual C++
	Makefile Project	Visual C++
	Shared Items Project	Visual C++

Not finding what you are looking for?
[Open Visual Studio Installer](#)

Name:

Location:

Solution name:

Create directory for solution

Create new Git repository

Solution Explorer

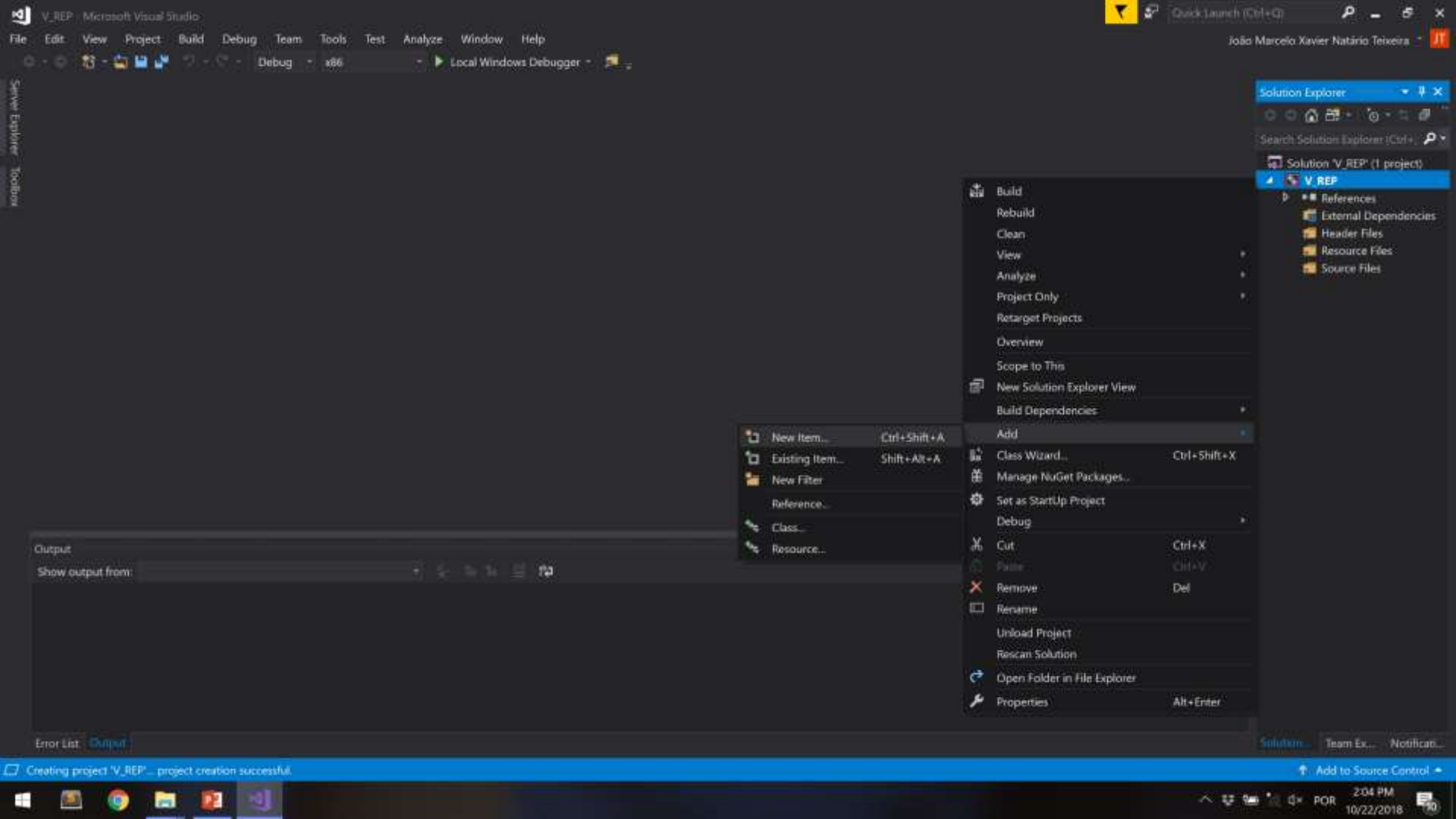
network

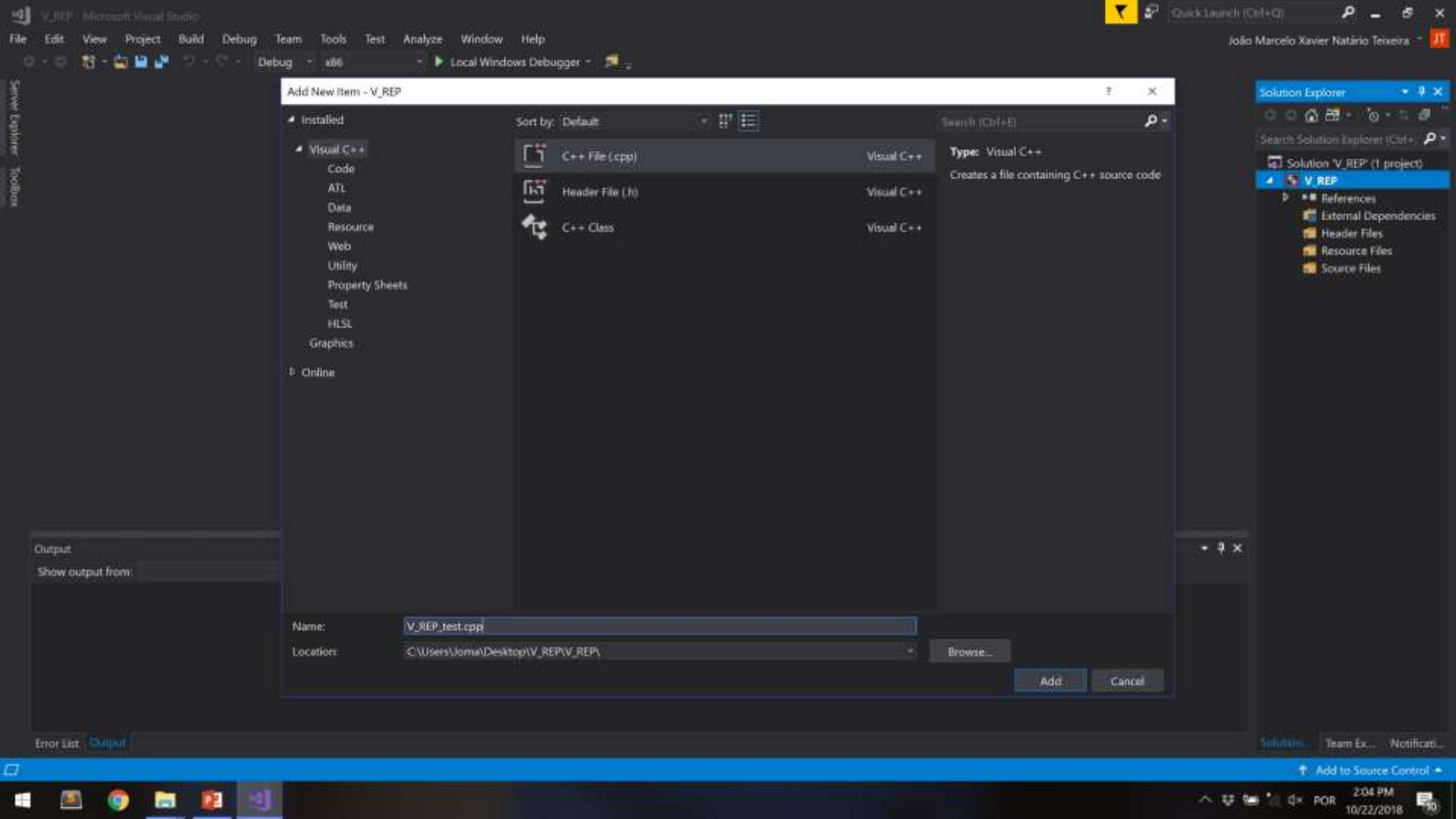
Solution... Team Ex... Notificati...

Output

Show output from:

Error List [Output](#)





Add New Item - V_REP

Installed

Visual C++

Code

ATL

Data

Resource

Web

Utility

Property Sheets

Test

HLSL

Graphics

Online

Sort by: Default



C++ File (.cpp)

Visual C++



Header File (.h)

Visual C++



C++ Class

Visual C++

Search (Ctrl+E)

Type: Visual C++

Creates a file containing C++ source code

Name:

V_REP_test.cpp

Location:

C:\Users\Joma\Desktop\V_REP\V_REP

Browse...

Add

Cancel

Output

Show output from:

Error List

Output

Solution...

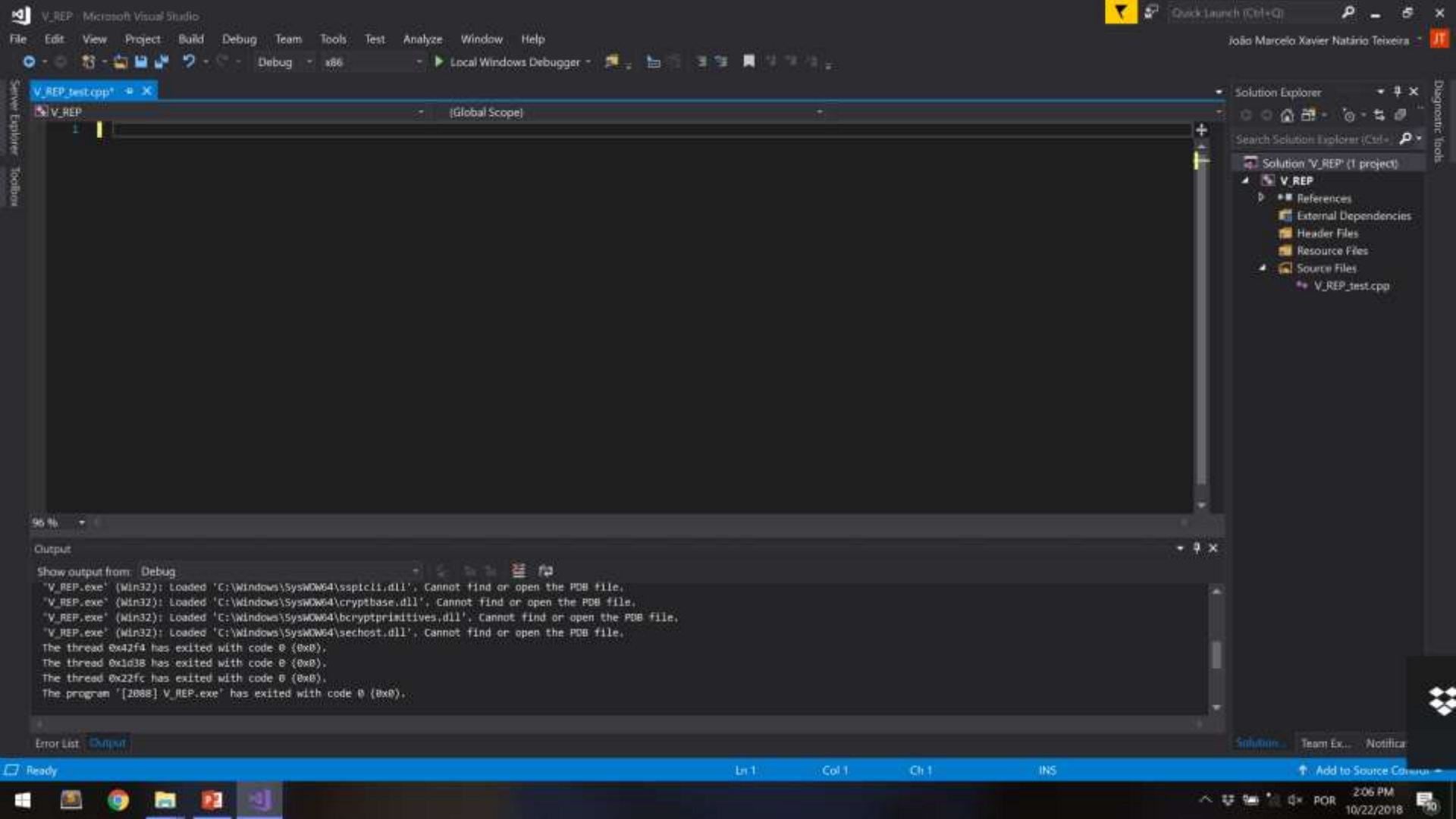
Team Ex...

Notificat...

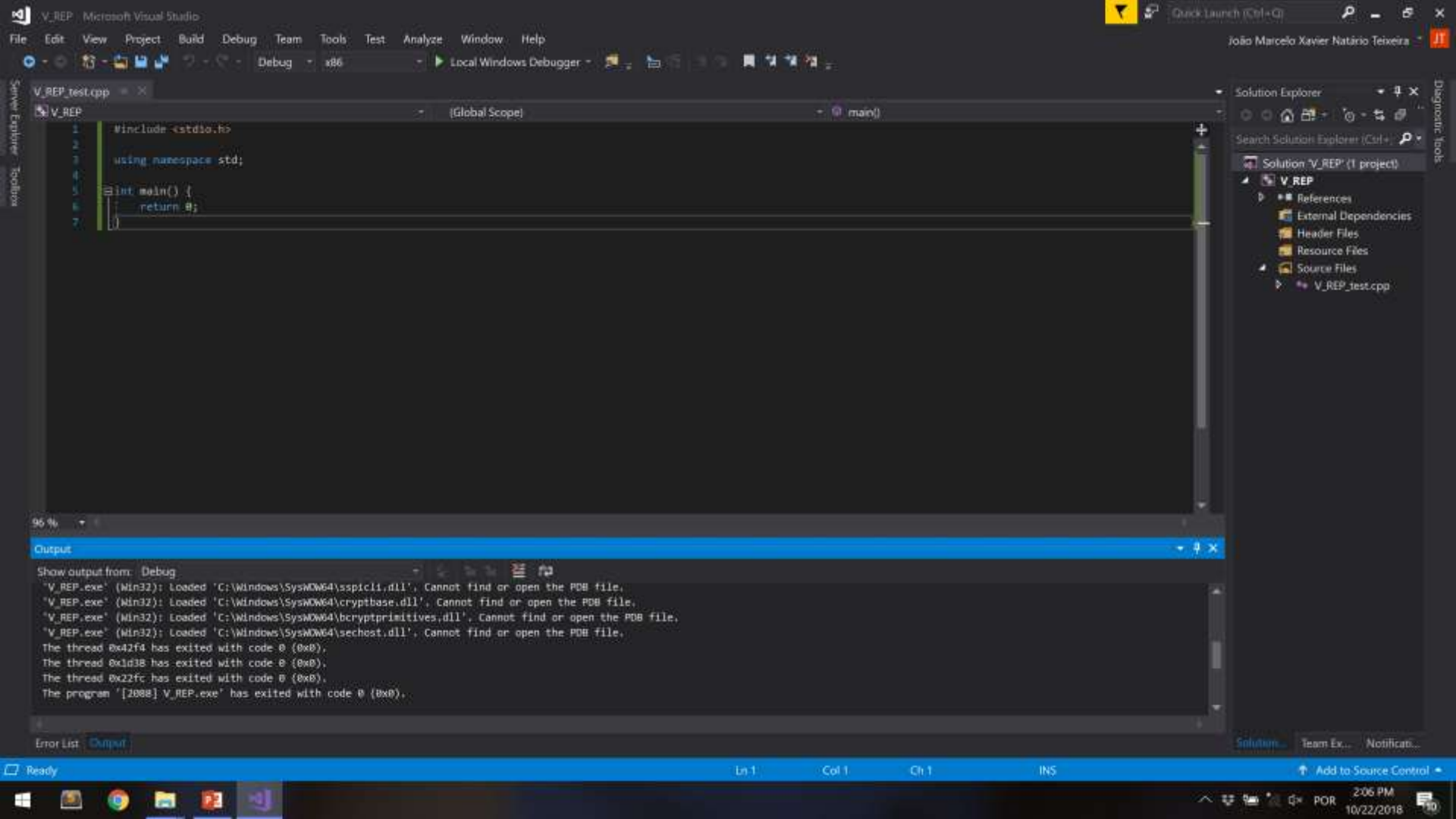
↑ Add to Source Control

2:04 PM

10/22/2018



All right?



Practice 2: accessing the image through API

1°) integrate kinect to the scene and associate it with Pioneer

2°) configure visual studio with OpenCV and V-REP API








3°) access kinect image by external API

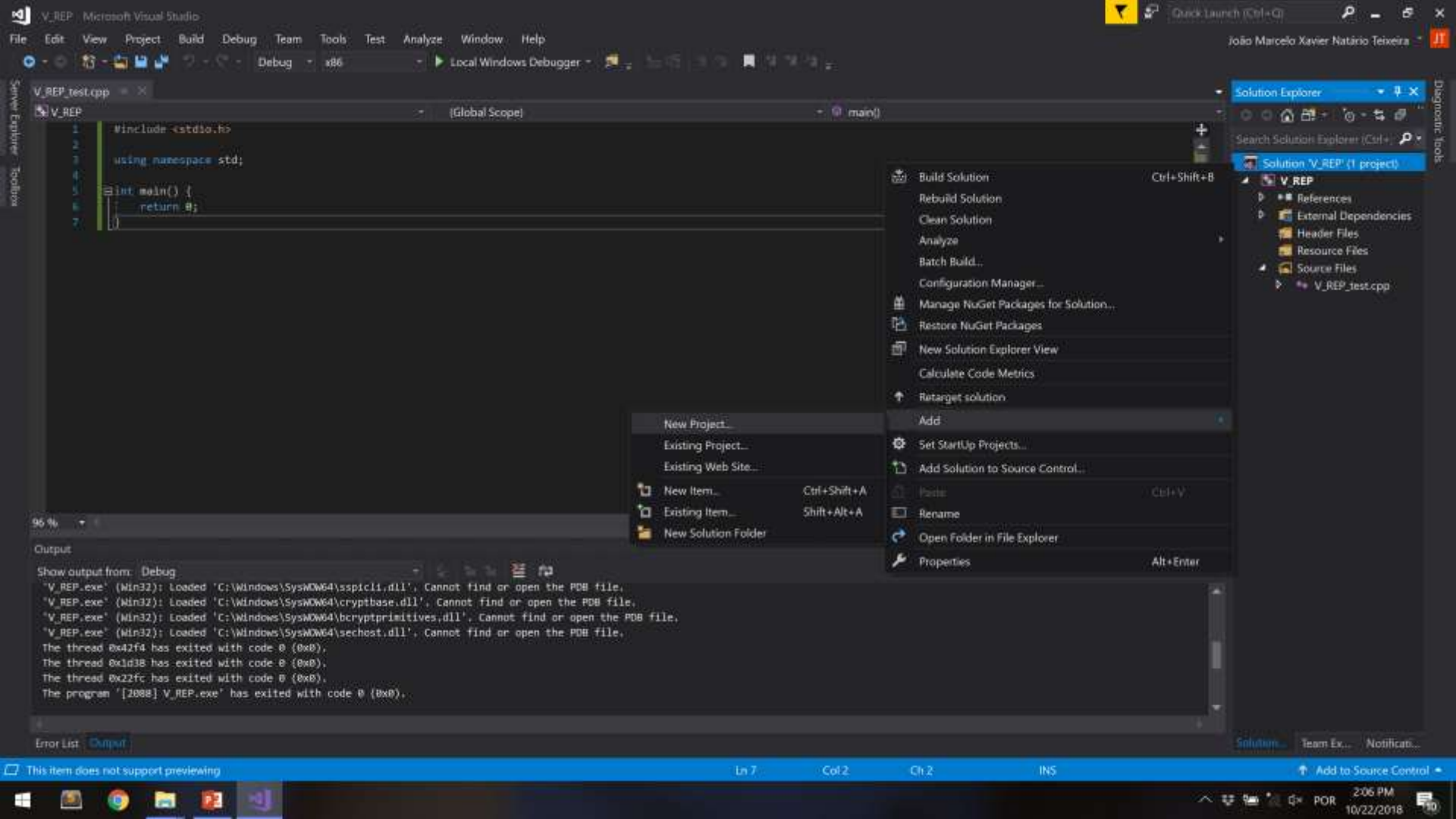
Dependencies folder



/v-rep

- C:\Program Files\V-REP3\V-REP_PRO_EDU\programming

 blueZeroBindings	10/21/2018 10:44	File folder	
 common	10/21/2018 10:44	File folder	
 include	10/21/2018 10:44	File folder	
 remoteApi	10/21/2018 10:44	File folder	
 remoteApiBindings	10/21/2018 10:44	File folder	
 v_repMath	10/21/2018 10:44	File folder	
 readme.txt	1/12/2018 2:59 PM	Text Document	9 KB



V_REP_test.cpp [Global Scope] main()

```
1 #include <stdio.h>
2
3 using namespace std;
4
5 int main() {
6     return 0;
7 }
```

Solution Explorer

Search Solution Explorer (Ctrl+)

Solution 'V_REP' (1 project)

- V_REP
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - V_REP_test.cpp

- Build Solution (Ctrl+Shift+B)
- Rebuild Solution
- Clean Solution
- Analyze
- Batch Build...
- Configuration Manager...
- Manage NuGet Packages for Solution...
- Restore NuGet Packages
- New Solution Explorer View
- Calculate Code Metrics
- Retarget solution
- Add
- Set StartUp Projects...
- Add Solution to Source Control...
- Paste (Ctrl+V)
- Rename
- Open Folder in File Explorer
- Properties (Alt+Enter)

- New Project...
- Existing Project...
- Existing Web Site...
- New Item... (Ctrl+Shift+A)
- Existing Item... (Shift+Alt+A)
- New Solution Folder

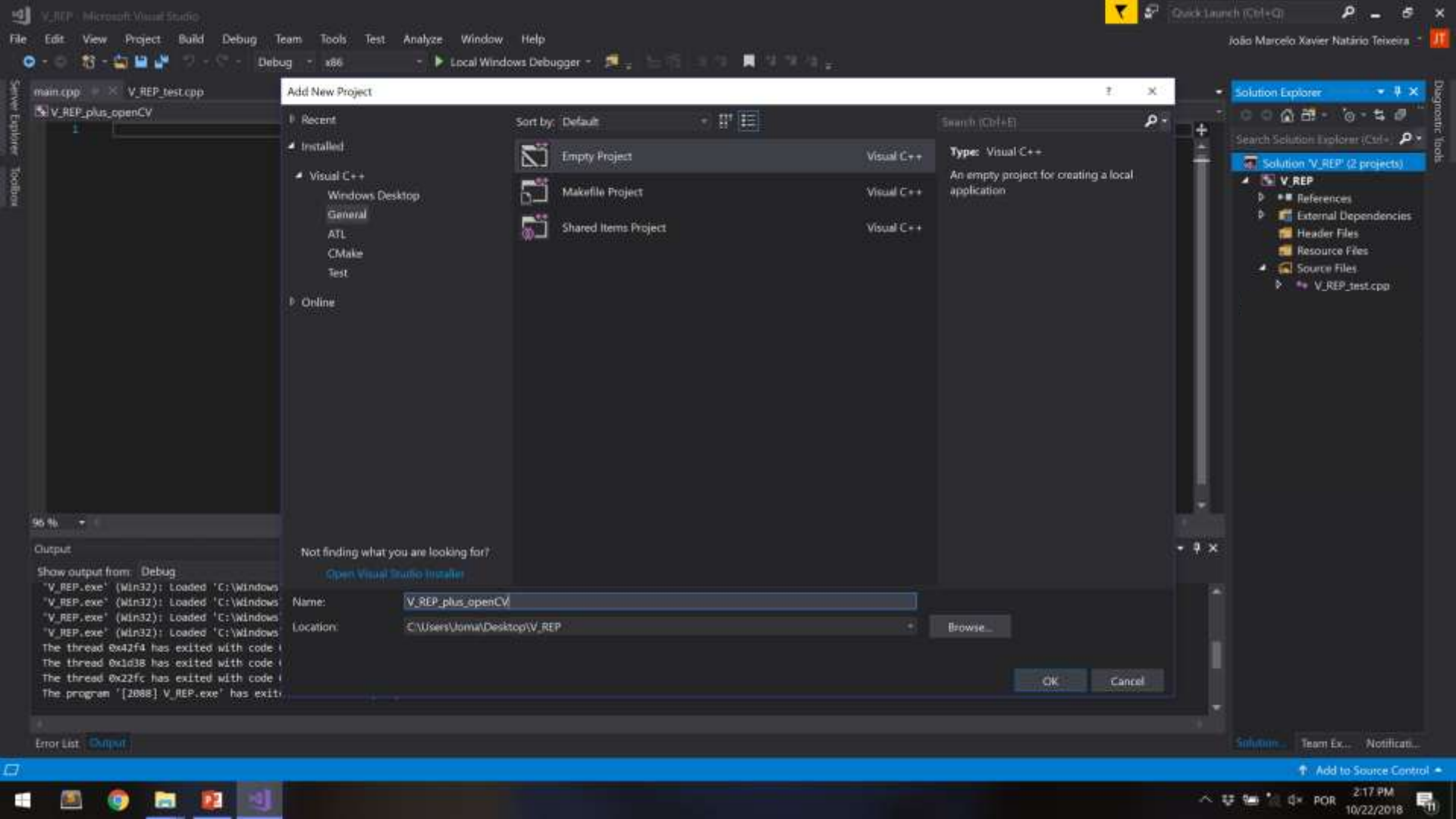
96 %

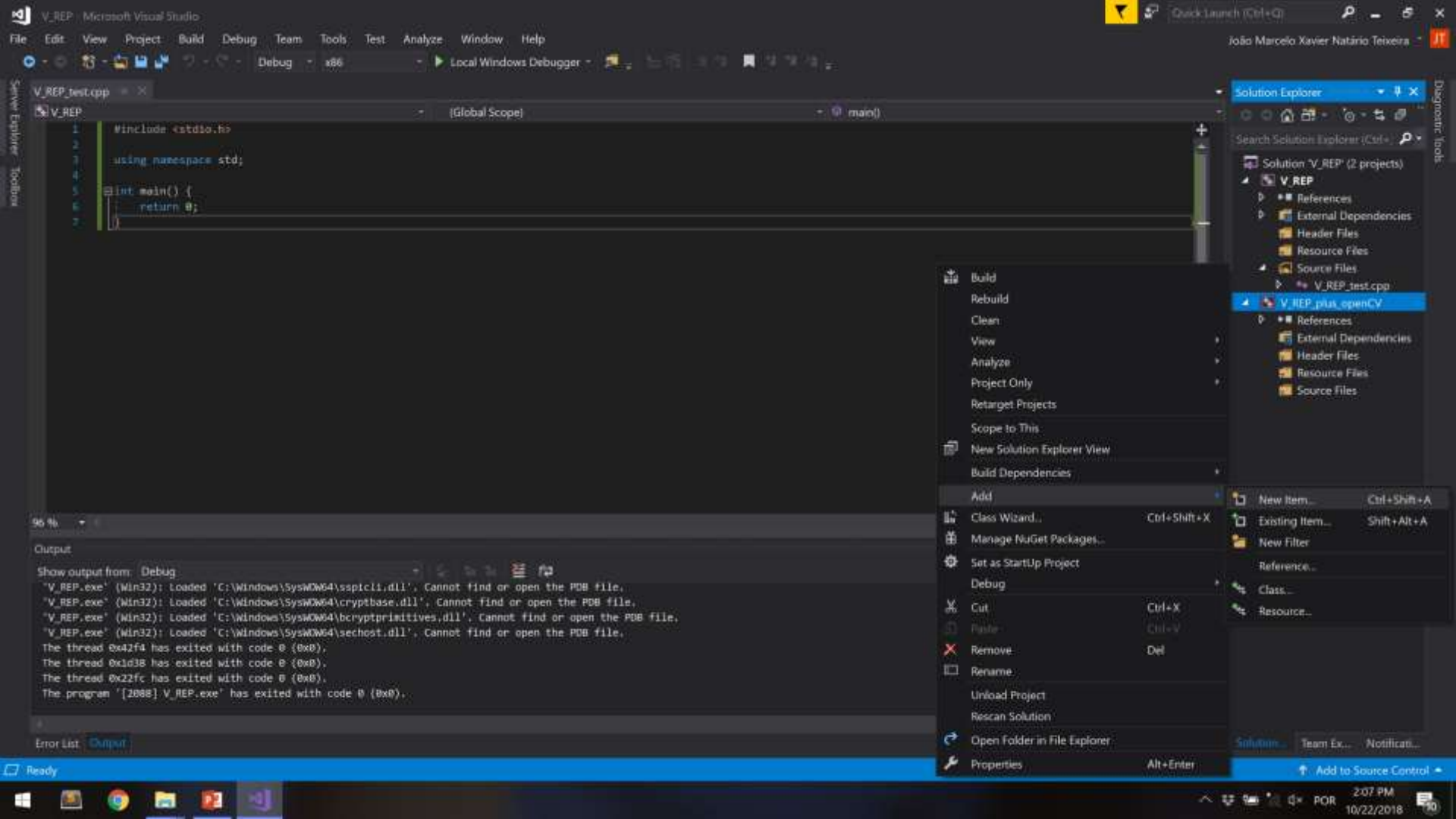
Output

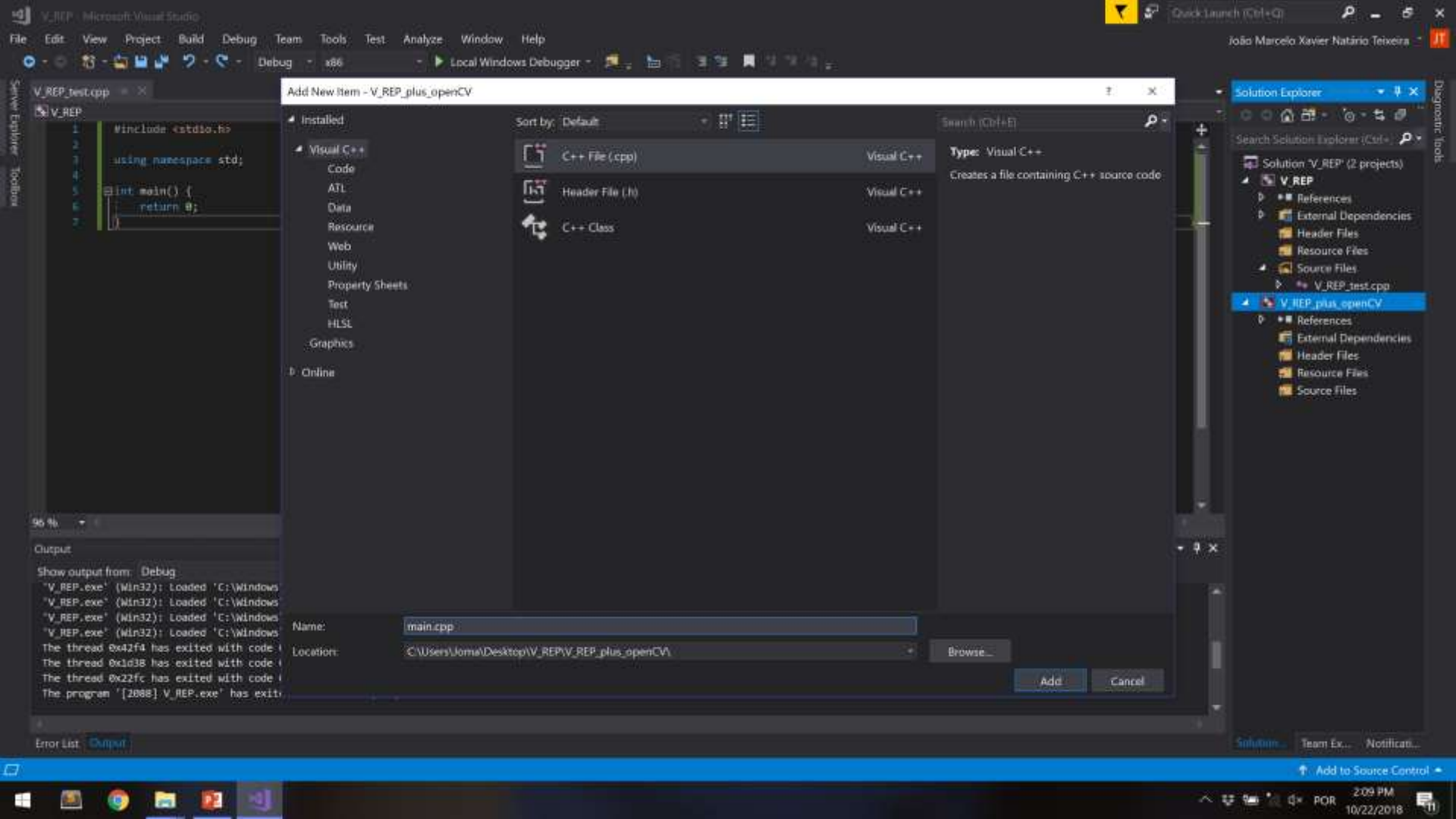
Show output from: Debug

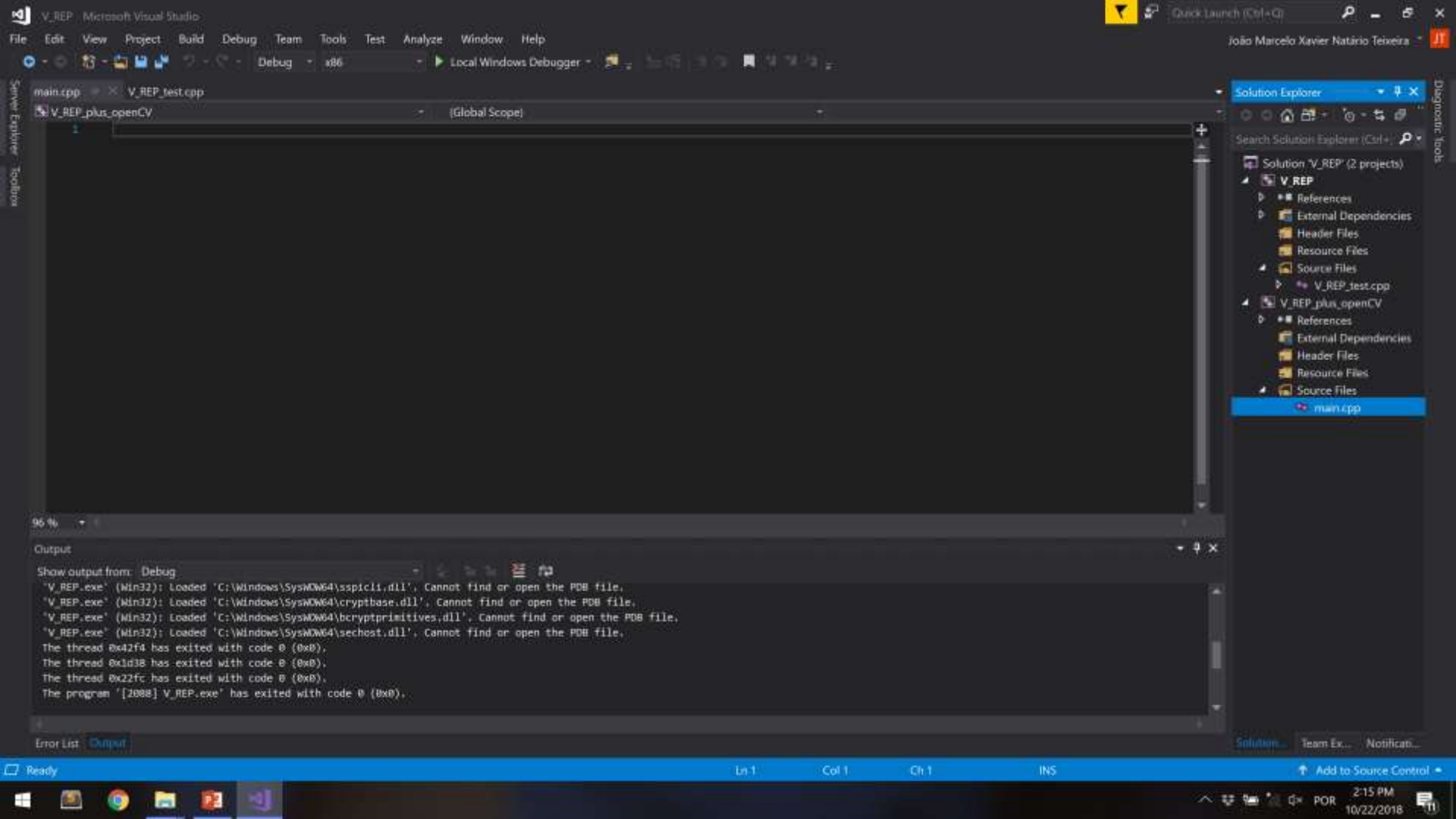
"V_REP.exe" (Win32): Loaded 'C:\Windows\System32\sspic11.dll'. Cannot find or open the PDB file.
 "V_REP.exe" (Win32): Loaded 'C:\Windows\System32\cryptbase.dll'. Cannot find or open the PDB file.
 "V_REP.exe" (Win32): Loaded 'C:\Windows\System32\bcryptprimitives.dll'. Cannot find or open the PDB file.
 "V_REP.exe" (Win32): Loaded 'C:\Windows\System32\sechost.dll'. Cannot find or open the PDB file.
 The thread 0x42f4 has exited with code 0 (0x0).
 The thread 0x1d3b has exited with code 0 (0x0).
 The thread 0x22fc has exited with code 0 (0x0).
 The program '[2088] V_REP.exe' has exited with code 0 (0x0).

Error List



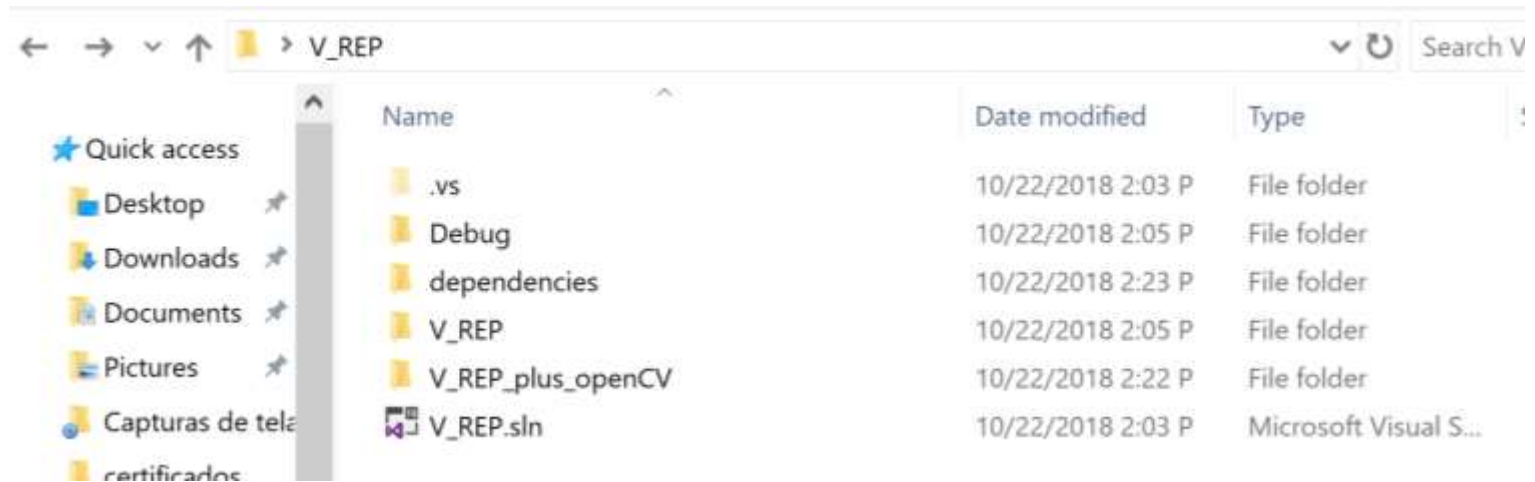


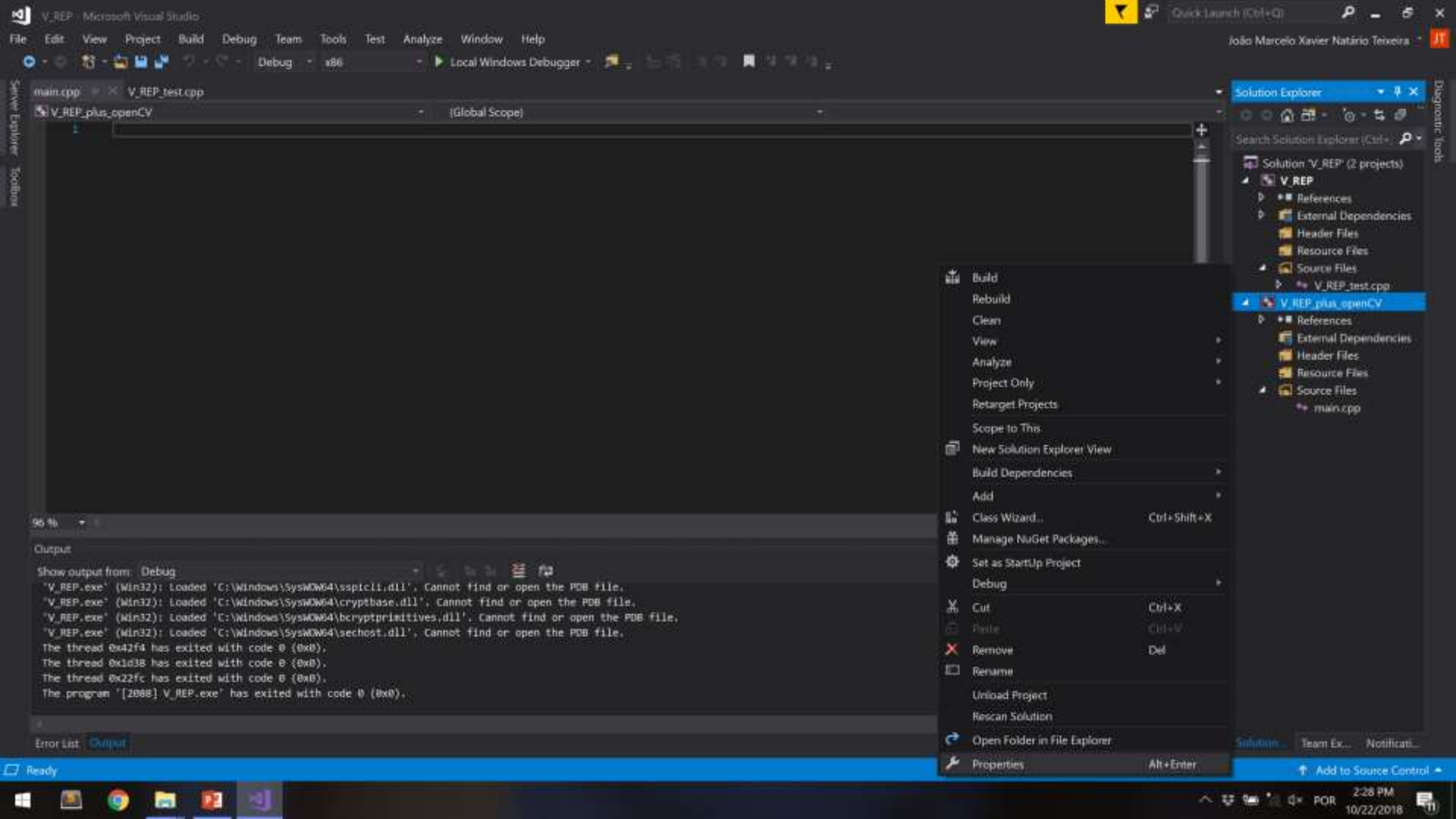


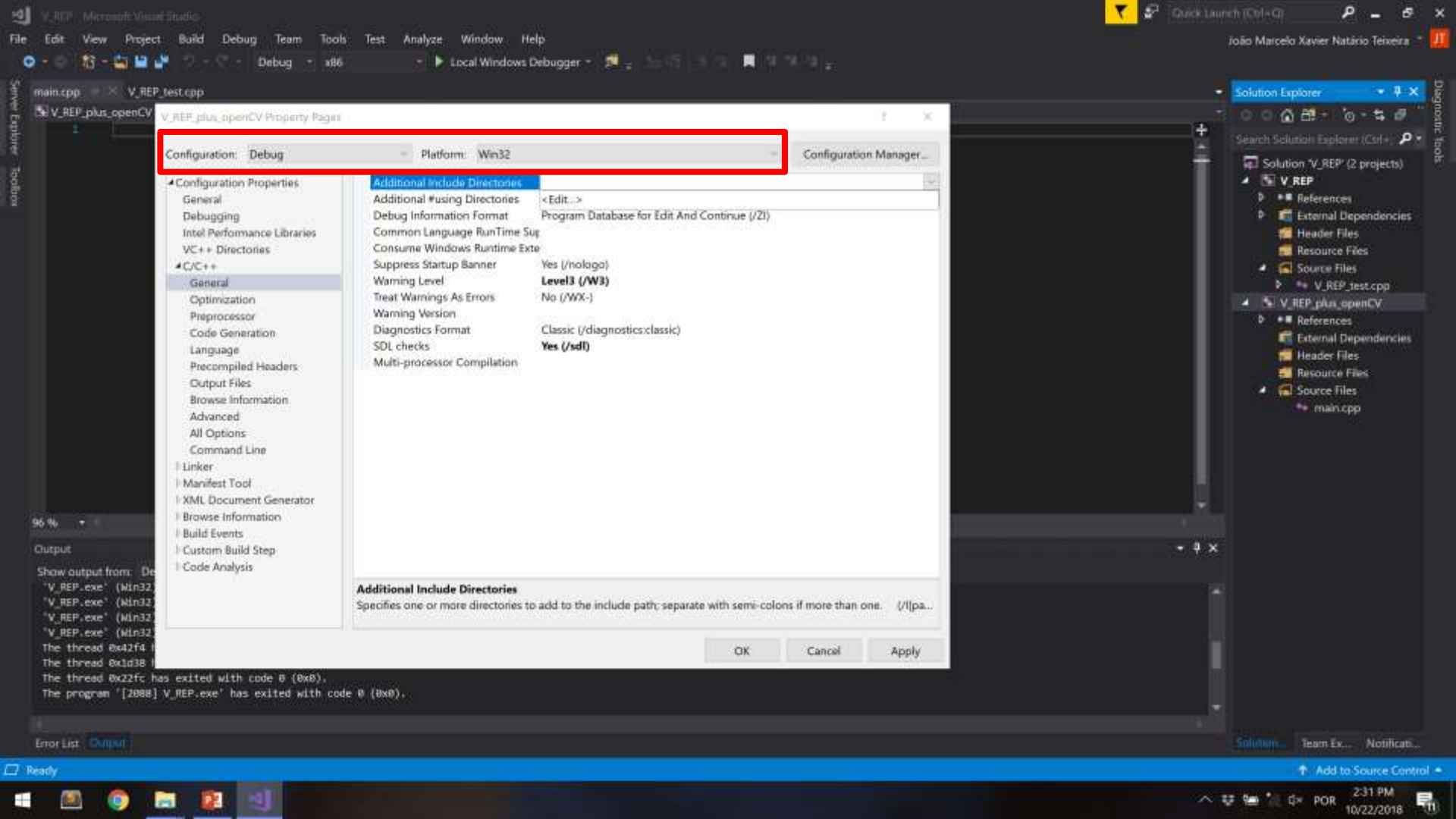


OBS

- \$(SolutionDir)







Configuration: Debug Platform: Win32 Configuration Manager...

- Configuration Properties
 - General
 - Debugging
 - Intel Performance Libraries
 - VC++ Directories
 - C/C++
 - General
 - Optimization
 - Preprocessor
 - Code Generation
 - Language
 - Precompiled Headers
 - Output Files
 - Browse Information
 - Advanced
 - All Options
 - Command Line
 - Linker
 - Manifest Tool
 - XML Document Generator
 - Browse Information
 - Build Events
 - Custom Build Step
 - Code Analysis

Additional Include Directories

Additional #using Directories <Edit...>
 Debug Information Format Program Database for Edit And Continue (/ZI)
 Common Language RunTime Sup
 Consume Windows Runtime Ext
 Suppress Startup Banner Yes (/nologo)
 Warning Level **Level3 (/W3)**
 Treat Warnings As Errors No (/WX-)
 Warning Version Classic (/diagnostics:classic)
 Diagnostics Format **Yes (/sdl)**
 Multi-processor Compilation

Additional Include Directories

Specifies one or more directories to add to the include path; separate with semi-colons if more than one. (/I|pa..)

OK Cancel Apply

96 %
 Output
 Show output from: De
 "V_REP.exe" (Win32
 "V_REP.exe" (Win32
 "V_REP.exe" (Win32
 "V_REP.exe" (Win32
 The thread 0x42f4
 The thread 0x1d38
 The thread 0x22fc has exited with code 0 (0x0).
 The program "[2088] V_REP.exe" has exited with code 0 (0x0).

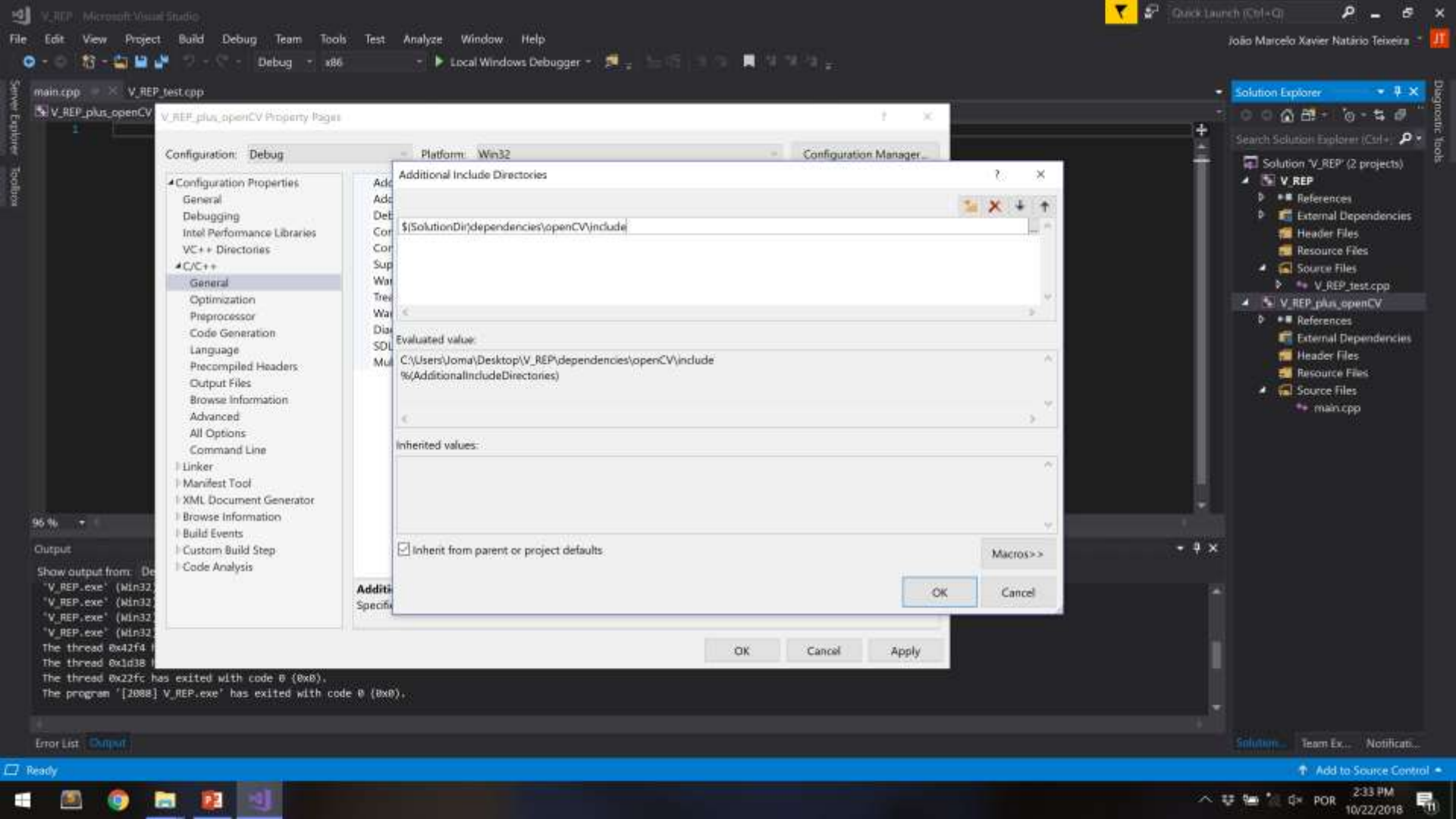
Error List Output

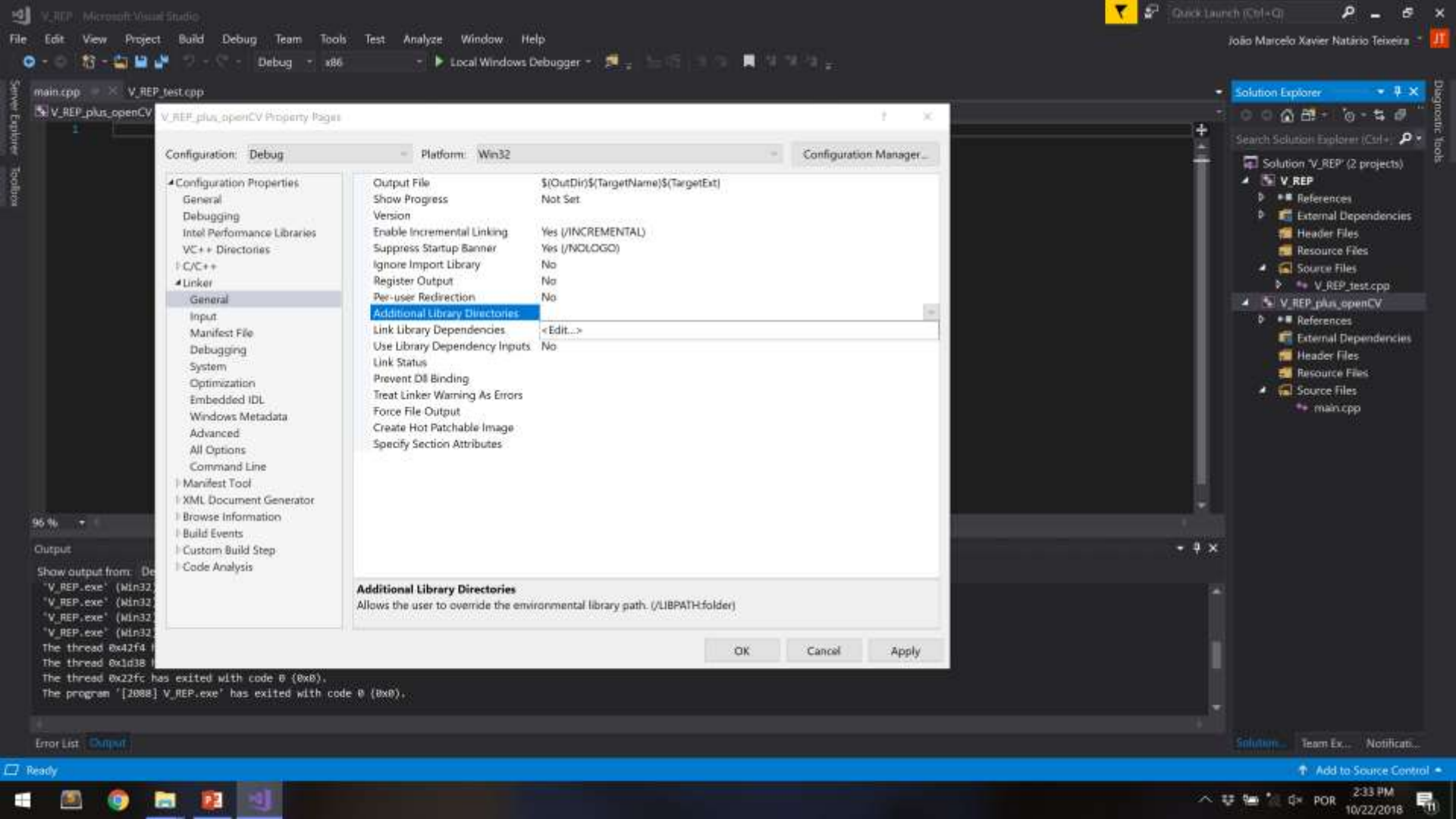
Solution Explorer

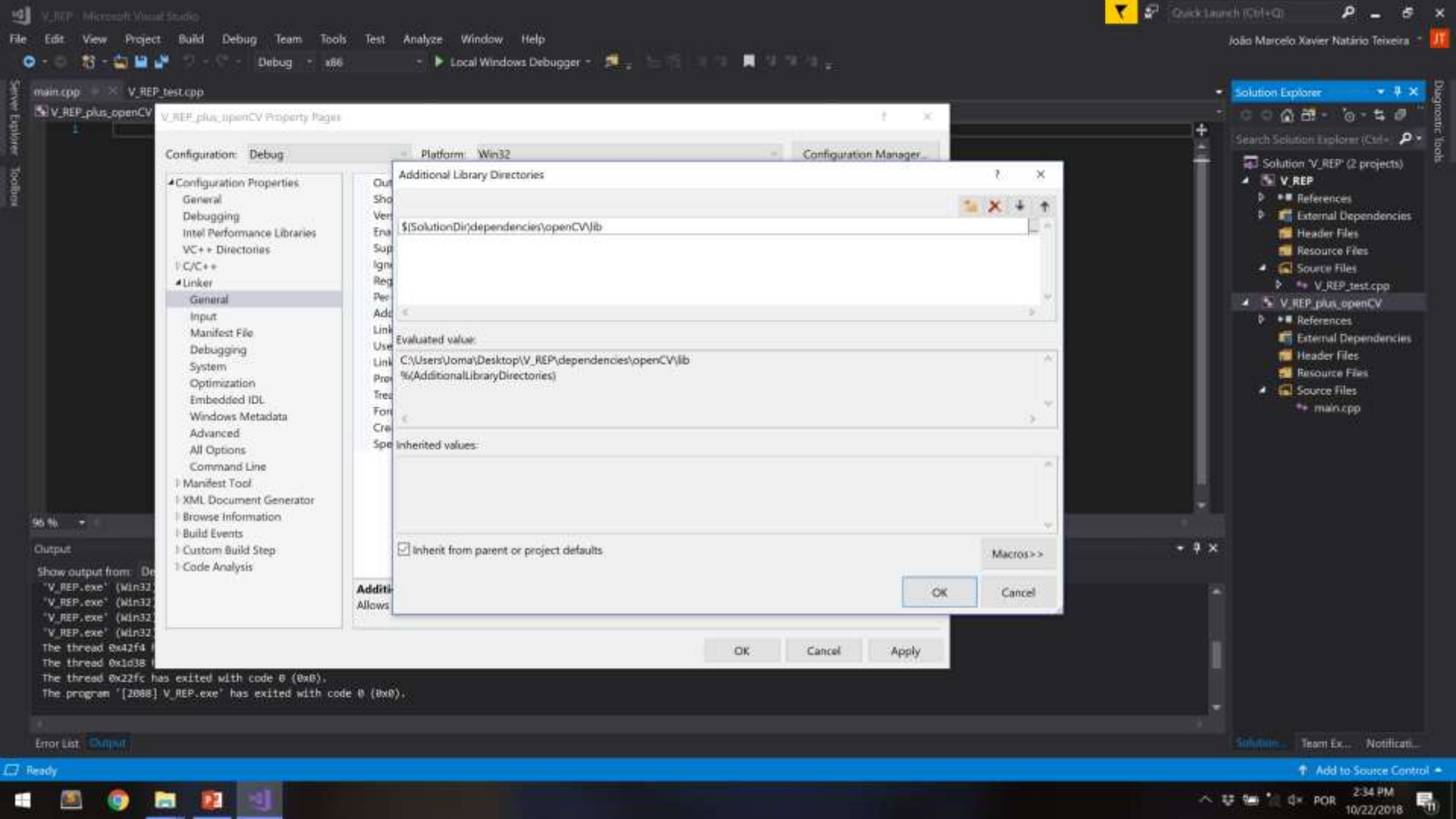
Search Solution Explorer (Ctrl+Q)

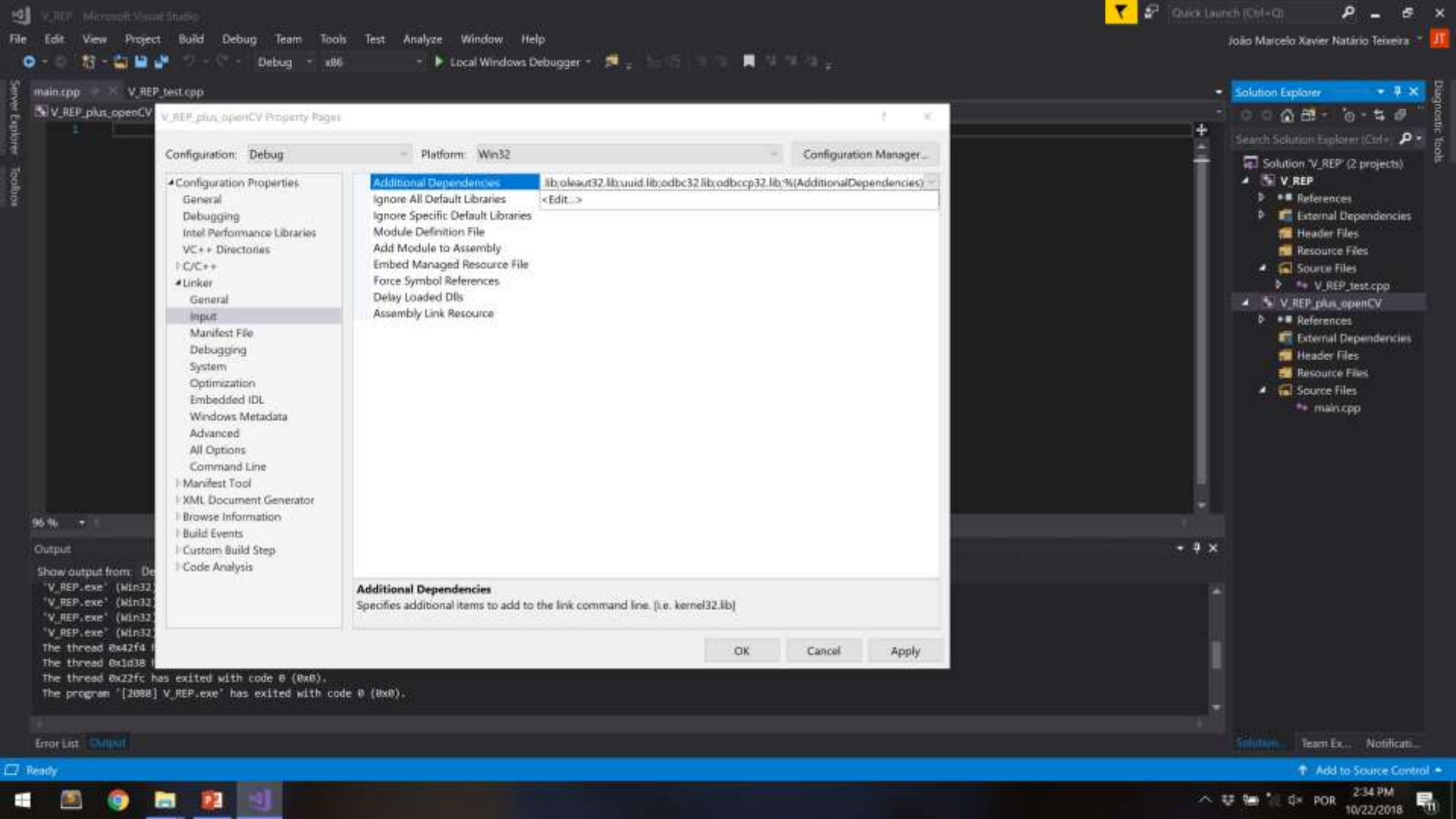
Solution 'V_REP' (2 projects)

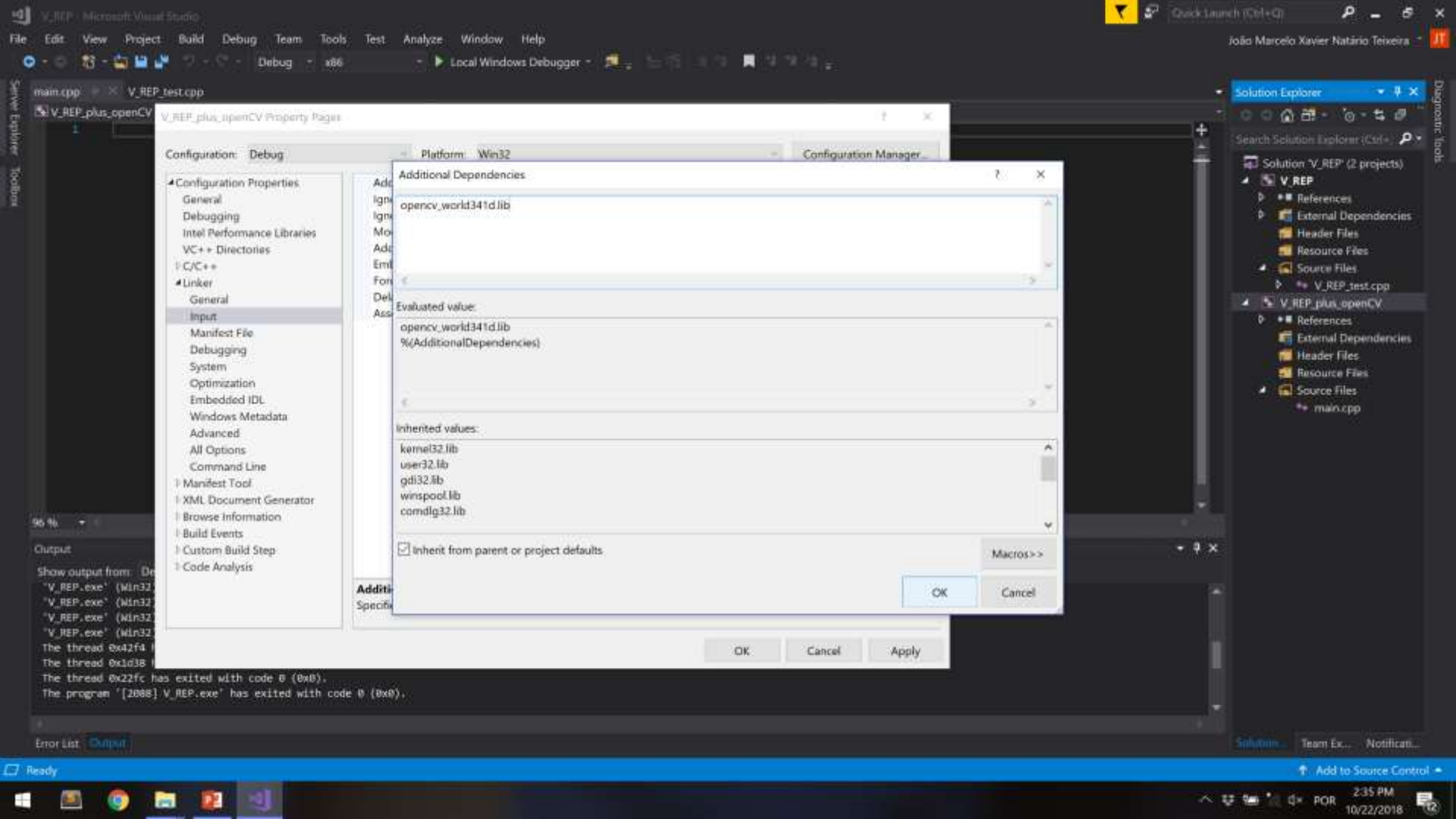
- V_REP
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - V_REP_test.cpp
- V_REP_plus_openCV
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - main.cpp

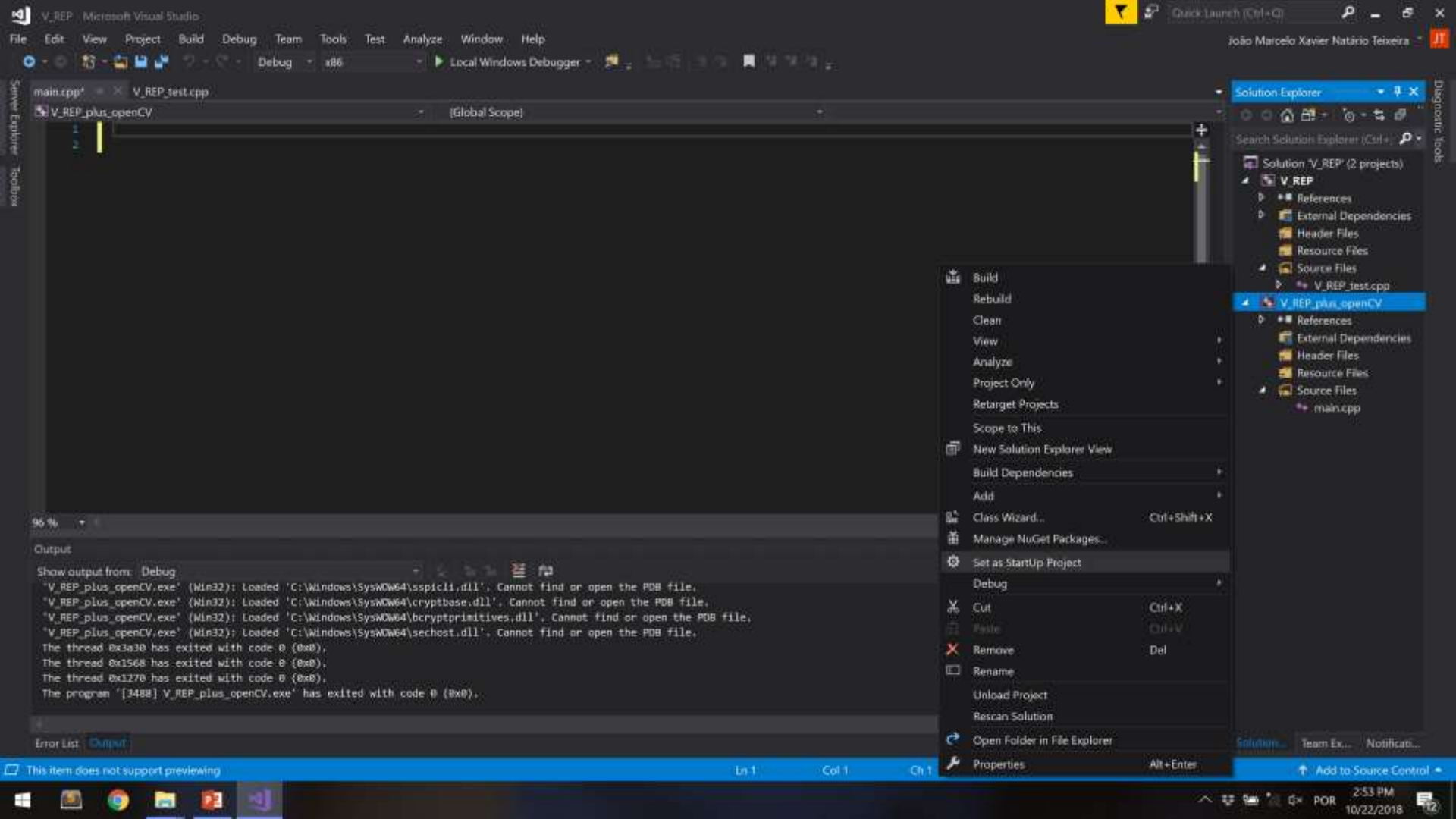
















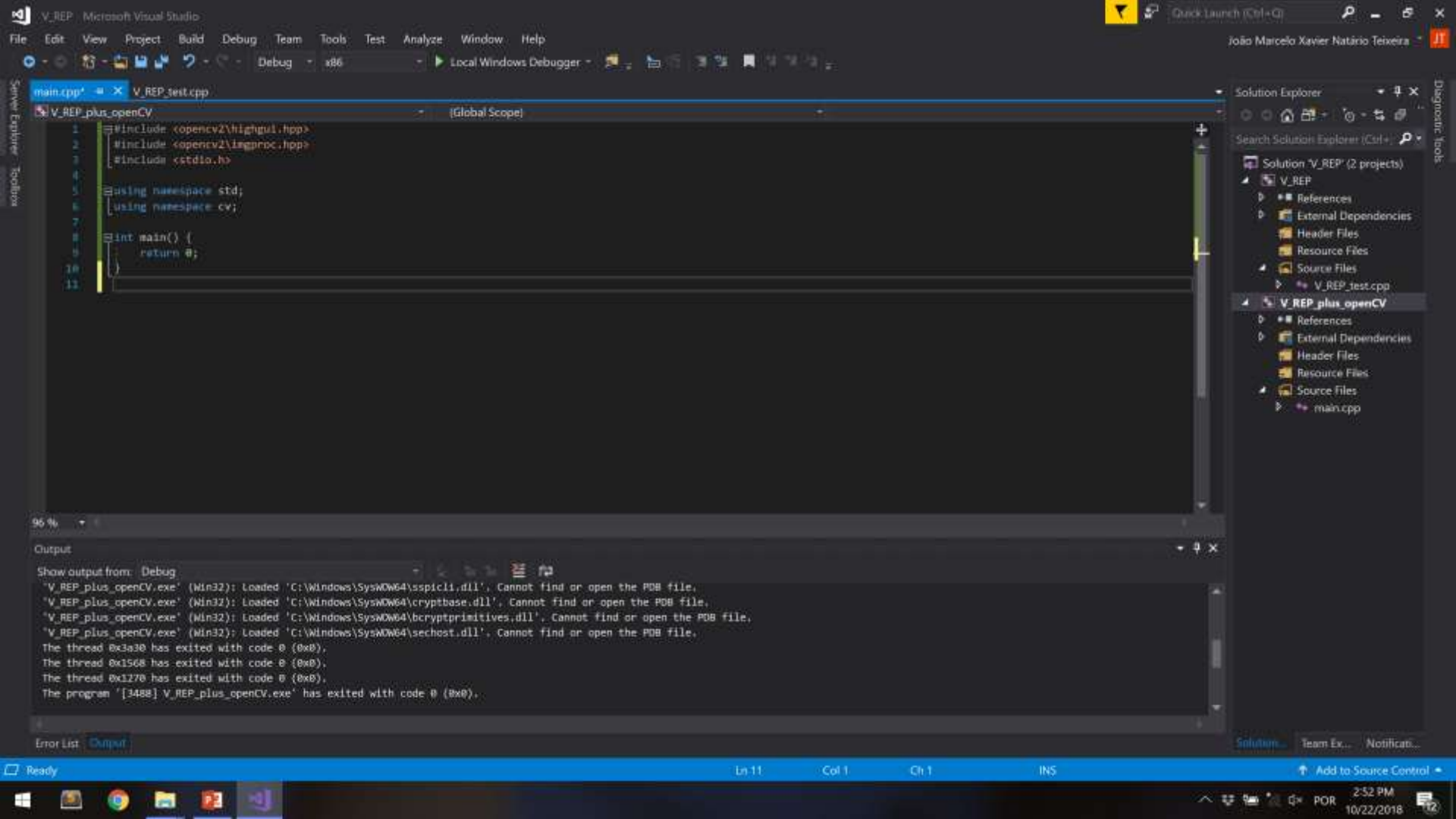




OBS

 Debug	10/24/2018 2:34 PM	File folder	
 x64	10/24/2018 9:15 A	File folder	
 main.cpp	10/26/2018 8:08 PM	C++ Source file	1 KB
 opencv_ffmpeg341_64.dll	2/23/2018 10:47 A	Application extens	17,631 KB
 opencv_world341d.dll	2/23/2018 10:58 A	Application extens	102,202 KB
 V_REP_plus_openCV.vcxproj	10/26/2018 7:35 PM	VC++ Project	8 KB
 V_REP_plus_openCV.vcxproj.filters	10/23/2018 9:05 PM	VC++ Project Filte...	2 KB
 V_REP_plus_openCV.vcxproj.user	10/22/2018 2:07 PM	Per-User Project O...	1 KB

All right?!

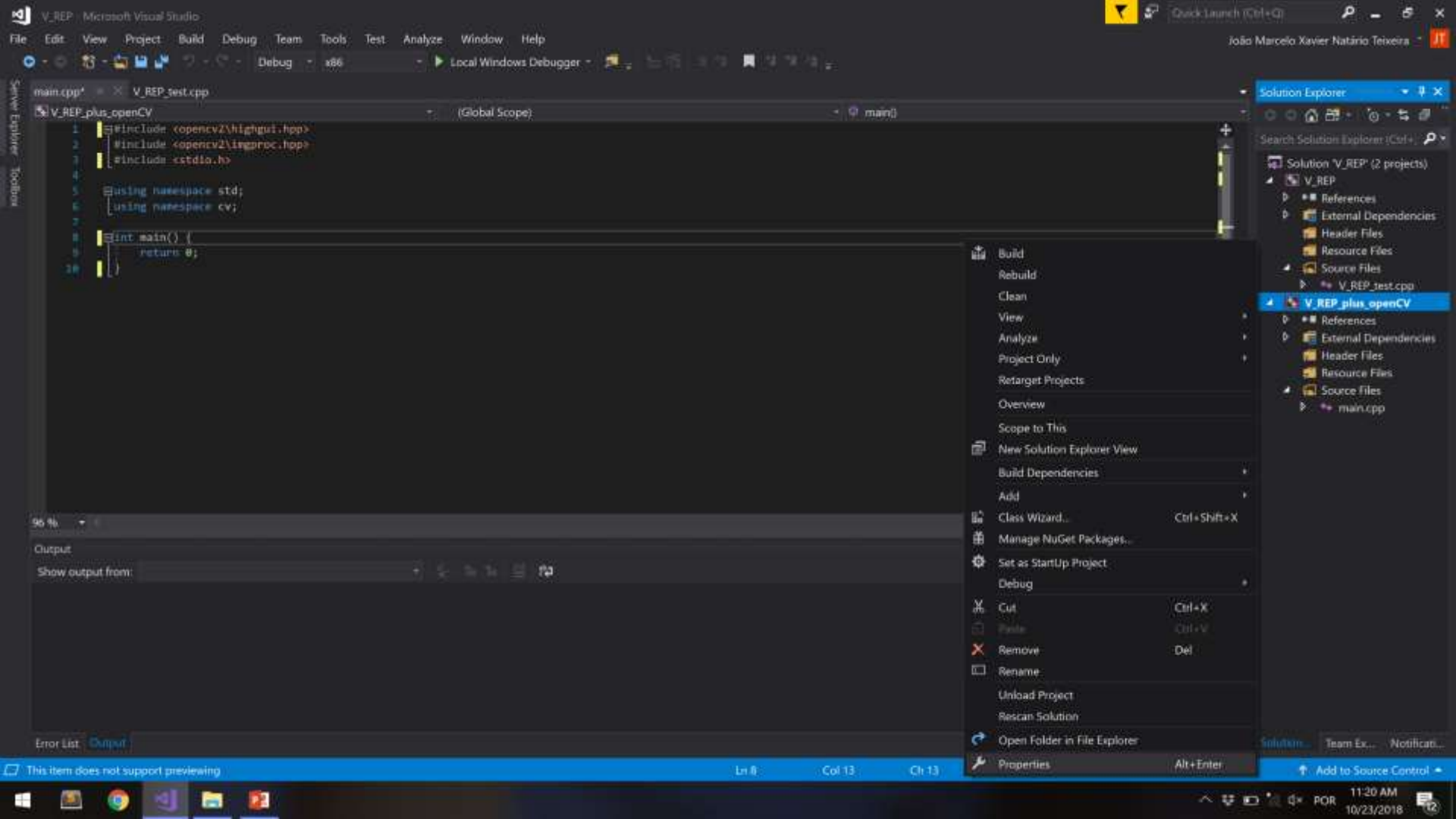


Practice 2: accessing the image through API

1°) integrate kinect to the scene and associate it with Pioneer

2°) configure visual studio with **OpenCV** and **V-REP API**

3°) access kinect image by external API



main.cpp* V_REP_test.cpp

V_REP_plus_openCV (Global Scope) main

```
1 #include <opencv2/highgui.hpp>
2 #include <opencv2/imgproc.hpp>
3 #include <stdio.h>
4
5 using namespace std;
6 using namespace cv;
7
8 int main() {
9     return 0;
10 }
```

Solution Explorer

Solution Explorer (Ctrl+Q)

- Solution 'V_REP' (2 projects)
 - V_REP
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - V_REP_test.cpp
 - V_REP_plus_openCV**
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - main.cpp

- Build
- Rebuild
- Clean
- View
- Analyze
- Project Only
- Retarget Projects
- Overview
- Scope to This
- New Solution Explorer View
- Build Dependencies
- Add
- Class Wizard... (Ctrl+Shift+X)
- Manage NuGet Packages...
- Set as StartUp Project
- Debug
- Cut (Ctrl+X)
- Paste (Ctrl+V)
- Remove (Del)
- Rename
- Unload Project
- Rescan Solution
- Open Folder in File Explorer
- Properties (Alt+Enter)

96 %

Output

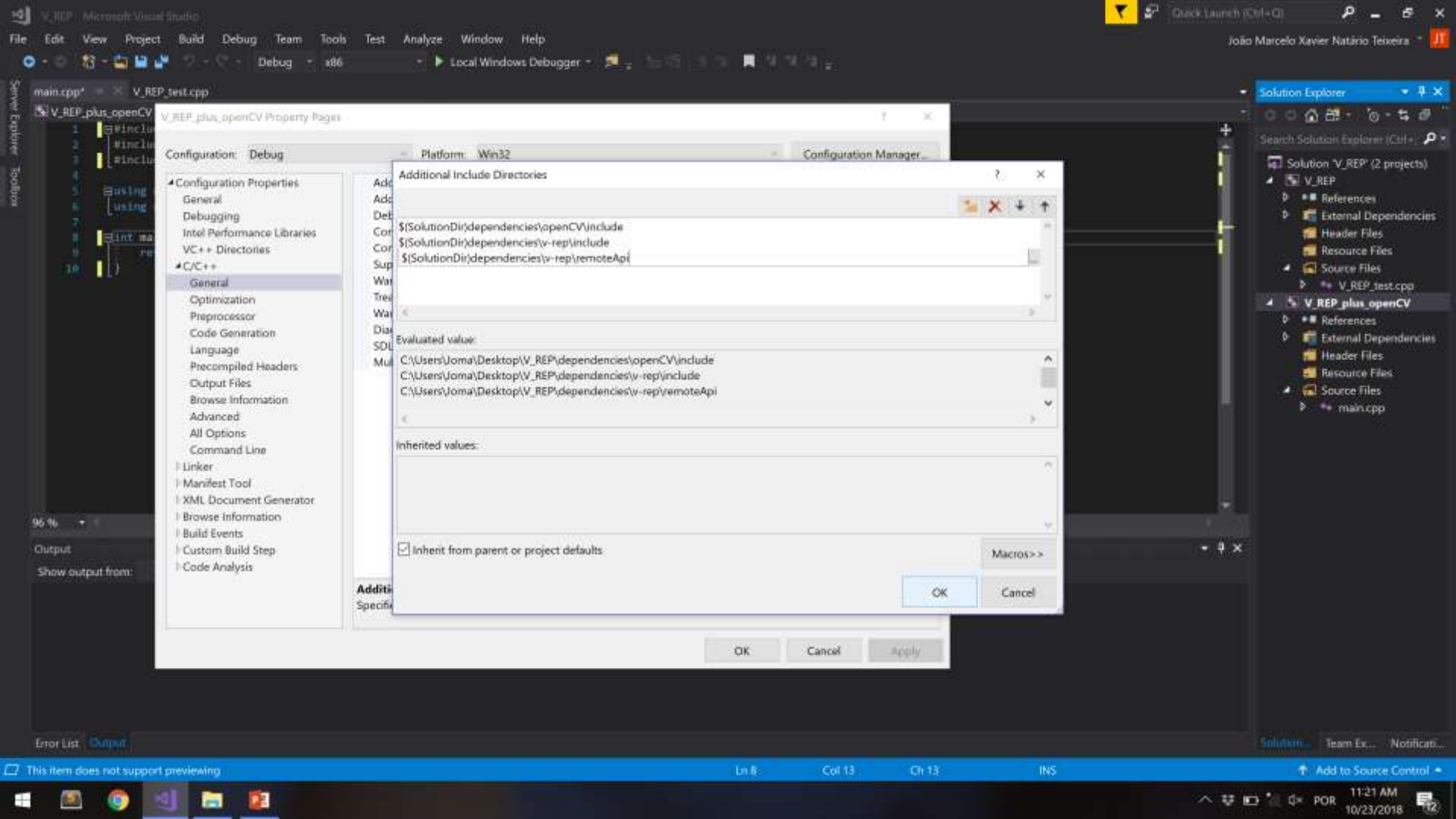
Show output from:

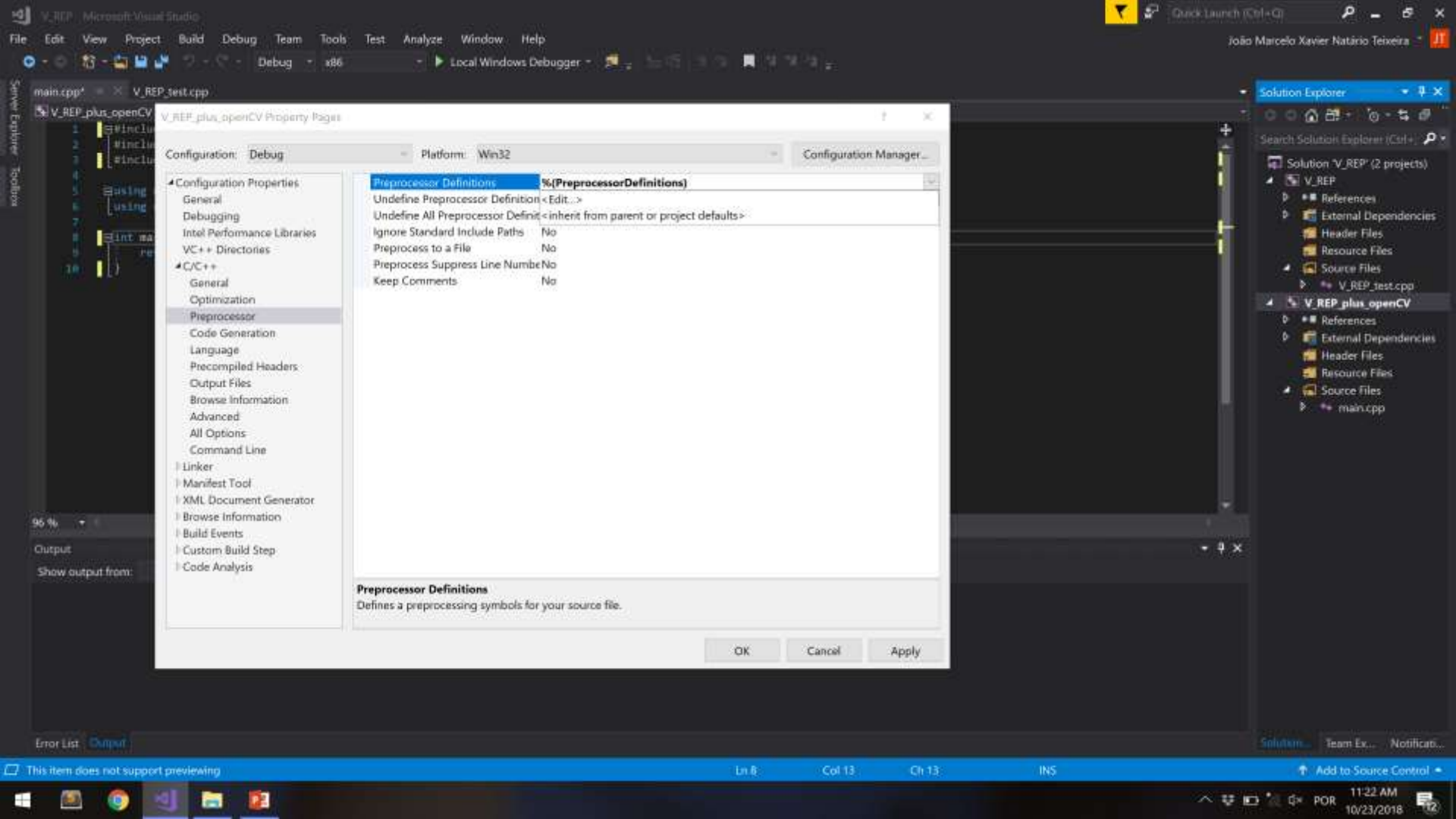
Error List Output

Ln 8 Col 13 Chr 13

Solution Team Ex... Notificati...

Add to Source Control





V_REF_plus_openCV Property Pages

Configuration: Debug Platform: Win32 Configuration Manager...

- Configuration Properties
 - General
 - Debugging
 - Intel Performance Libraries
 - VC++ Directories
 - C/C++
 - General
 - Optimization
 - Preprocessor**
 - Code Generation
 - Language
 - Precompiled Headers
 - Output Files
 - Browse Information
 - Advanced
 - All Options
 - Command Line
 - Linker
 - Manifest Tool
 - XML Document Generator
 - Browse Information
 - Build Events
 - Custom Build Step
 - Code Analysis

Preprocessor Definitions	
Preprocessor Definitions	%(PreprocessorDefinitions)
Undefined Preprocessor Definition < Edit... >	
Undefined All Preprocessor Definitio... < inherit from parent or project defaults >	
Ignore Standard Include Paths	No
Preprocess to a File	No
Preprocess Suppress Line Number	No
Keep Comments	No

Preprocessor Definitions
Defines a preprocessing symbols for your source file.

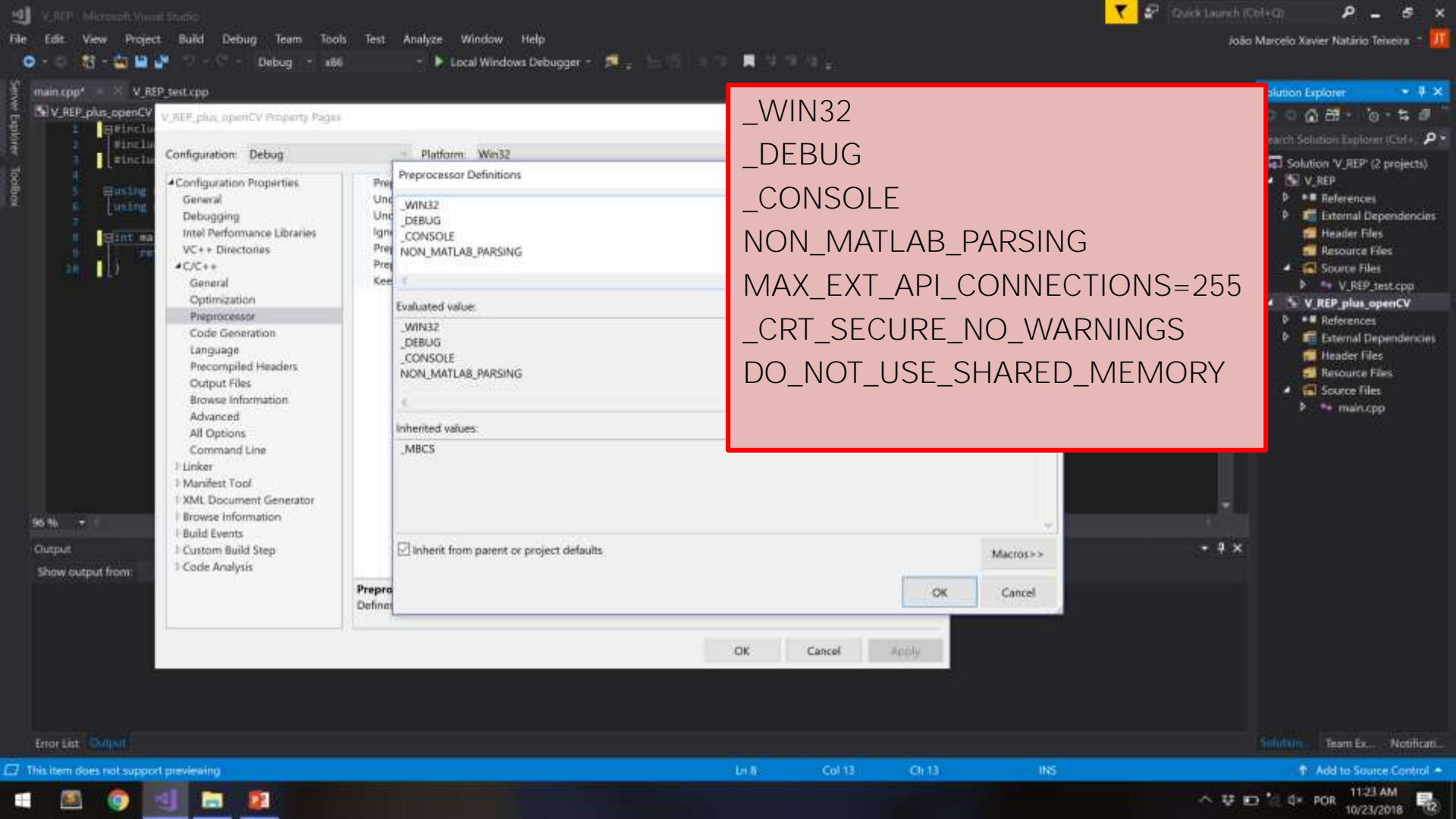
OK Cancel Apply

Solution Explorer

Search Solution Explorer (Ctrl+Q)

Solution 'V_REF' (2 projects)

- V_REF
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - V_REF_test.cpp
- V_REF_plus_openCV**
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - main.cpp



_WIN32
_DEBUG
_CONSOLE
NON_MATLAB_PARSING
MAX_EXT_API_CONNECTIONS=255
_CRT_SECURE_NO_WARNINGS
DO_NOT_USE_SHARED_MEMORY

V_REF_plus_openCV Property Pages

Configuration: Debug Platform: Win32

Preprocessor Definitions

_WIN32
_DEBUG
_CONSOLE
NON_MATLAB_PARSING

Evaluated value:
_WIN32
_DEBUG
_CONSOLE
NON_MATLAB_PARSING

Inherited values:
_MBCS

inherit from parent or project defaults

Macros >>
OK Cancel

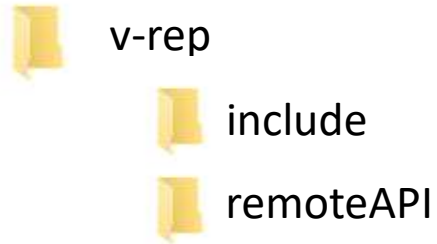
OK Cancel Apply

Solution Explorer

- Solution 'V_REF' (2 projects)
 - V_REF
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - V_REF_test.cpp
 - V_REF_plus_openCV
 - References
 - External Dependencies
 - Header Files
 - Resource Files
 - Source Files
 - main.cpp

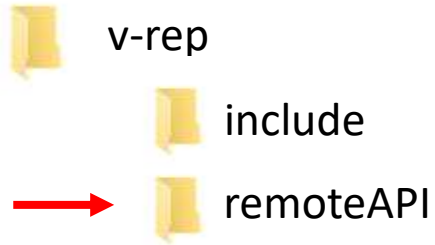
Practice 2: accessing the image through API

V-REP/dependencies/v-rep









Practice 2: accessing the image through API

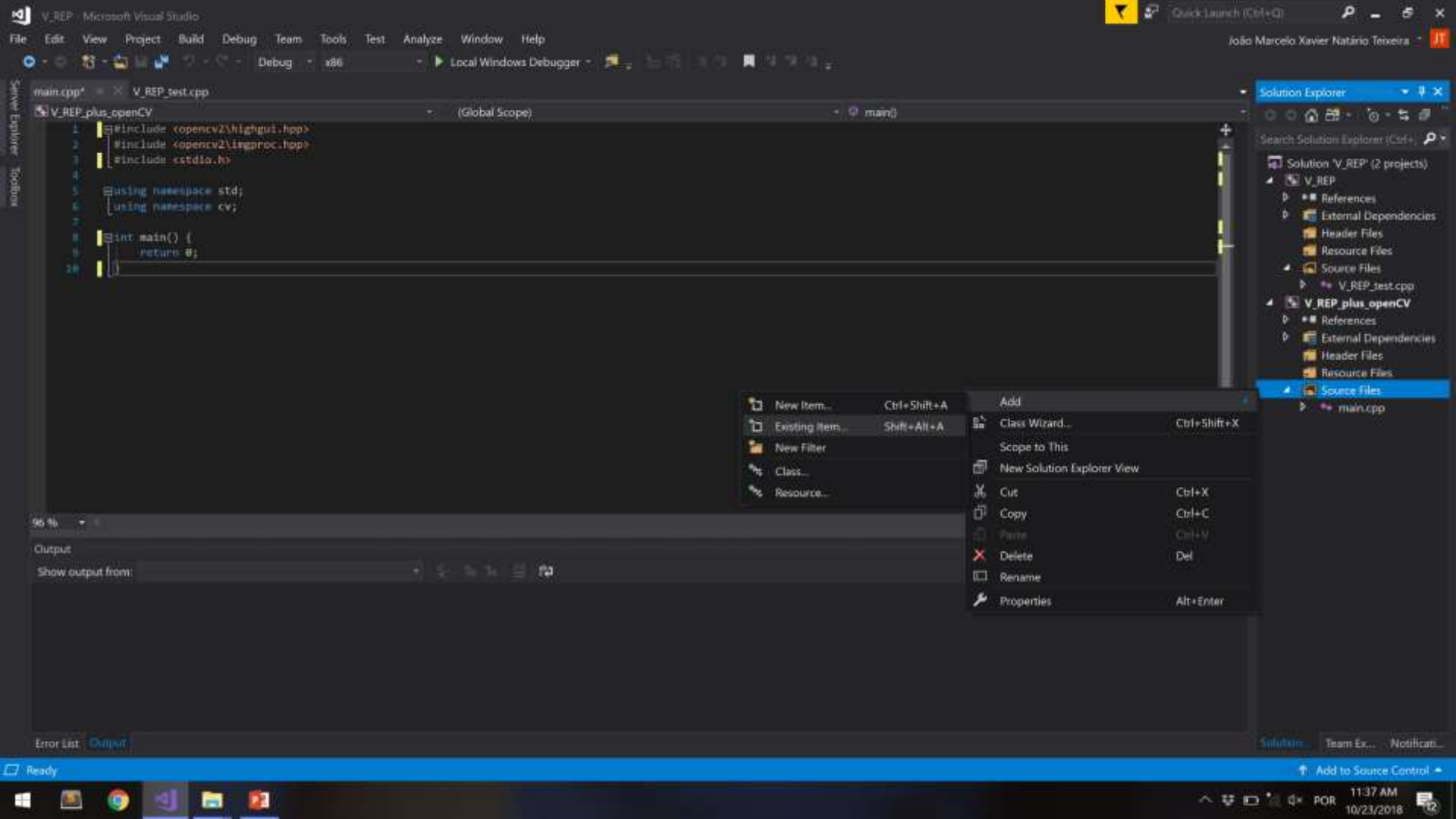
V-REP/dependencies/v-rep

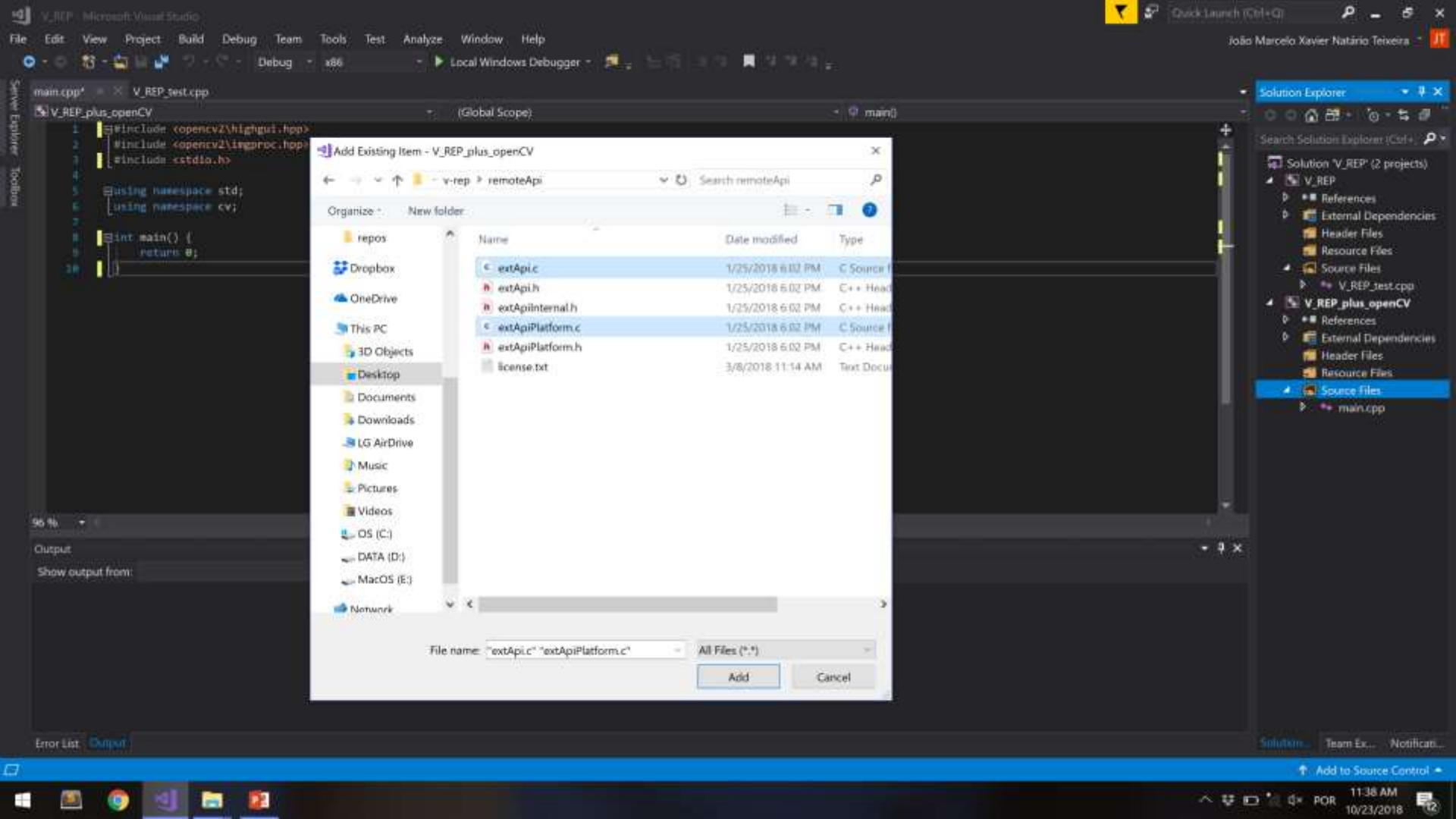


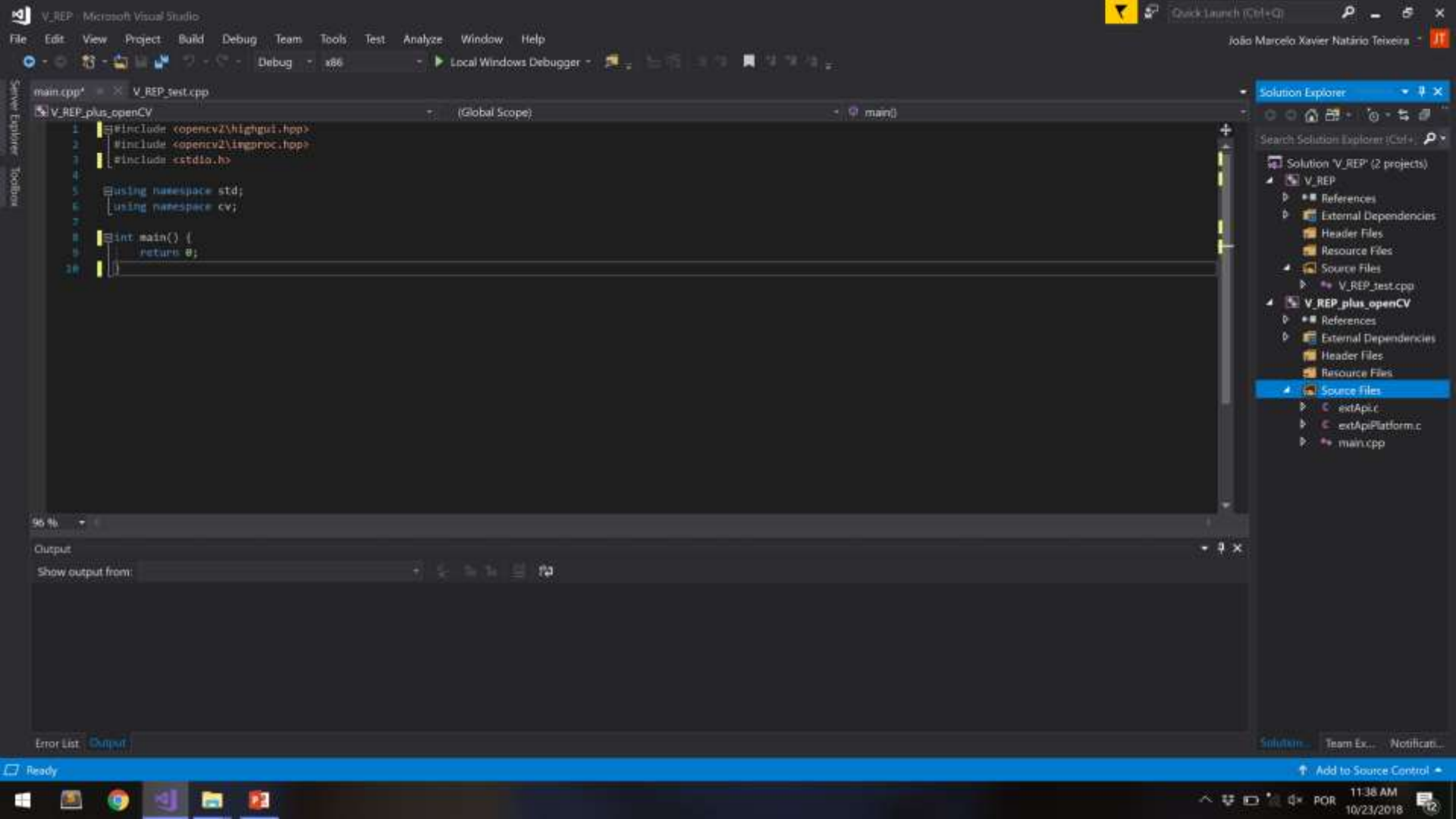
Practice 2: accessing the image through API

V-REP/dependencies/v-rep/remoteAPI

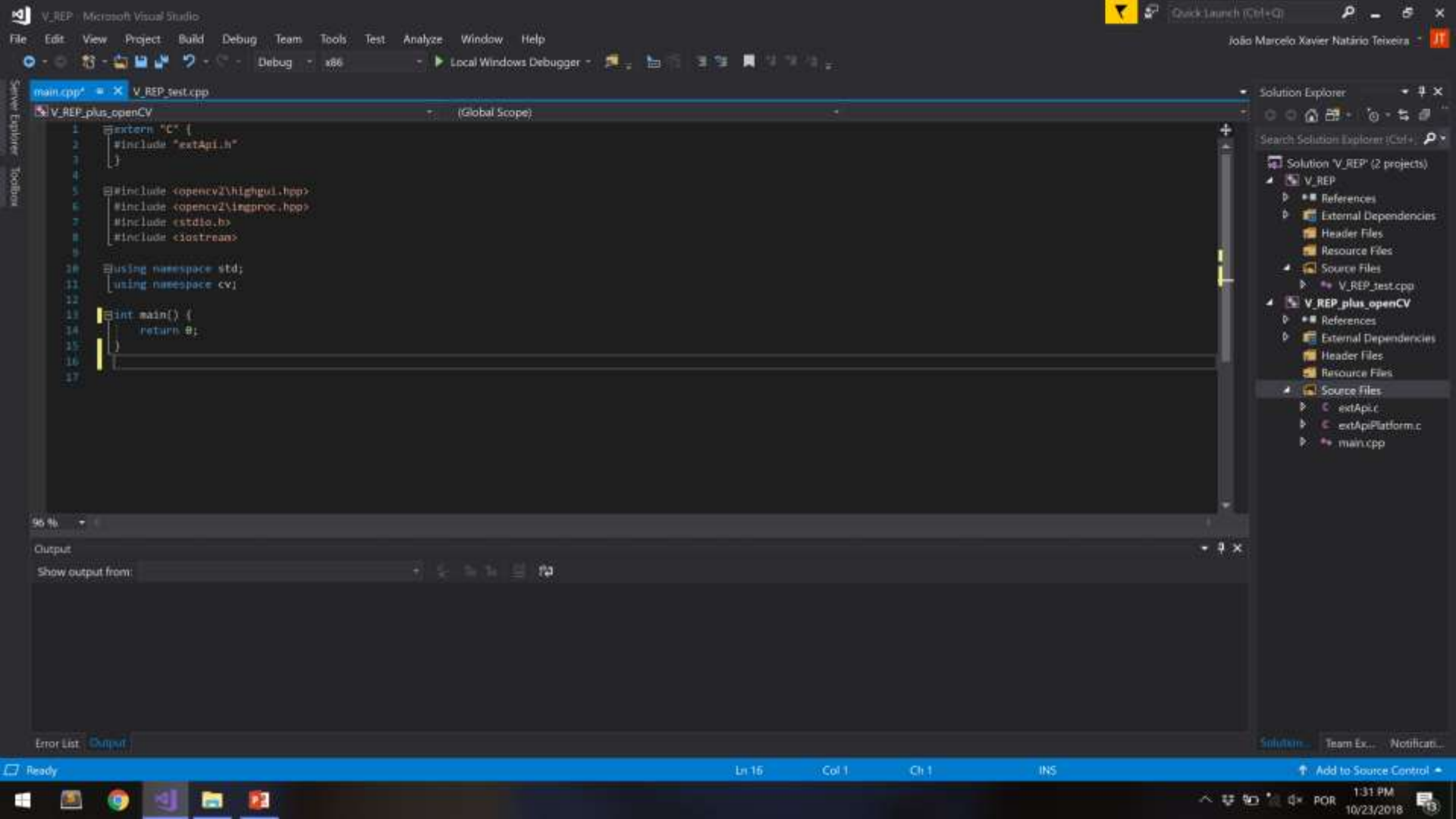
Name	Date modified	Type	Size
 extApi.c	1/25/2018 6:02 PM	C Source file	284 KB
 extApi.h	1/25/2018 6:02 PM	C++ Header file	27 KB
 extApiInternal.h	1/25/2018 6:02 PM	C++ Header file	3 KB
 extApiPlatform.c	1/25/2018 6:02 PM	C Source file	20 KB
 extApiPlatform.h	1/25/2018 6:02 PM	C++ Header file	4 KB
 license.txt	3/8/2018 11:14 AM	Text Document	3 KB







All right?!



Practice 2: accessing the image through API

1°) integrate kinect to the scene and associate it with Pioneer

2°) configure visual studio with OpenCV and V-REP API

3°) access kinect image by external API

Practice 2: accessing the image through API

Embedded script - kinect

```
function sysCall_init()  
    depthCam=sim.getObjectHandle('kinect_depth')  
    depthView=sim.floatingViewAdd(0.9,0.9,0.2,0.2,0)  
    sim.adjustView(depthView,depthCam,64)  
  
    colorCam=sim.getObjectHandle('kinect_rgb')  
    colorView=sim.floatingViewAdd(0.69,0.9,0.2,0.2,0)  
    sim.adjustView(colorView,colorCam,64)  
end
```

Help links

- **V-REP manual:**

<http://www.coppeliarobotics.com/helpFiles/>

- **Remote API functions (C/C++):**

<http://www.coppeliarobotics.com/helpFiles/en/remoteApiFunctions.htm>

```

3  #include "extApi.h"
4  }
5
6  #include <opencv2/highgui/highgui.hpp>
7  #include <opencv2/imgproc/imgproc.hpp>
8  #include <stdio.h>
9  #include <iostream>
10
11  #using namespace std;
12  #using namespace cv;
13
14  #int main(int argc, char **argv) {
15      int colorCam = 0;
16      string serverIP = "127.0.0.1";
17      int serverPort = 19997;
18      int resolution[2];
19      SimsIChar *image_vrep;
20
21      simsFinish(-1);
22      int clientID = //simsStart
23                  //simsGetObjectHandle
24
25      while (clientID != -1) {
26          //simsGetVisionSensorImage
27          Mat image = Mat(resolution[1], resolution[0], CV_8UC3, image_vrep);
28          cvtColor(image, image, COLOR_RGB2BGR);
29
30          flip(image, image, 0);
31          imshow("v-rep image", image);
32          waitKey(1);
33      }
34      system("pause");
35  }

```


V_REP (Running) - Microsoft Visual Studio

File Edit View Project Build Debug Team Tools Test Analyze Window Help

João Marcelo Xavier Natário Teixeira

Process: C:\Users\Uoma\Desktop\V-rep\bin\Debug\V_REP_image_only.exe

commands.cp
V_REP_image

1
2
3
4
5
6
7
8
9
10
11
12
13
14
15
16
17
18
19
20
21
22
23
24
25
26
27

96 %

Watch 1

Name

Output from: Debug

V_REP_image_only.exe (Win32): Loaded 'C:\Windows\System32\Locale.nls'. Cannot find or open the PDB file.

V_REP_image_only.exe (Win32): Loaded 'C:\Windows\System32\CoreMessaging.dll'. Cannot find or open the PDB file.

V_REP_image_only.exe (Win32): Loaded 'C:\Windows\System32\ntmarta.dll'. Cannot find or open the PDB file.

V_REP_image_only.exe (Win32): Loaded 'C:\Windows\System32\WinTypes.dll'. Cannot find or open the PDB file.

V_REP_image_only.exe (Win32): Loaded 'C:\Windows\System32\WinTypes.dll'. Cannot find or open the PDB file.

V_REP_image_only.exe (Win32): Unloaded 'C:\Windows\System32\WinTypes.dll'.

Diagnostic Tools

Diagnostics session: 7 seconds

10s

Events

Process Memory (MB)

CPU (% of all processors)

Summary Events Memory Usage CPU Usage

Events

Show Events (0 of 0)

Memory Usage

Take Snapshot

Enable heap profiling (affects performance)

CPU Usage

Compiler Inline R... Compiler Optimiz... Call Stack Breakpoints Exception Settings Command Window Immediate Wind... Output

Ready

Add to Source Control

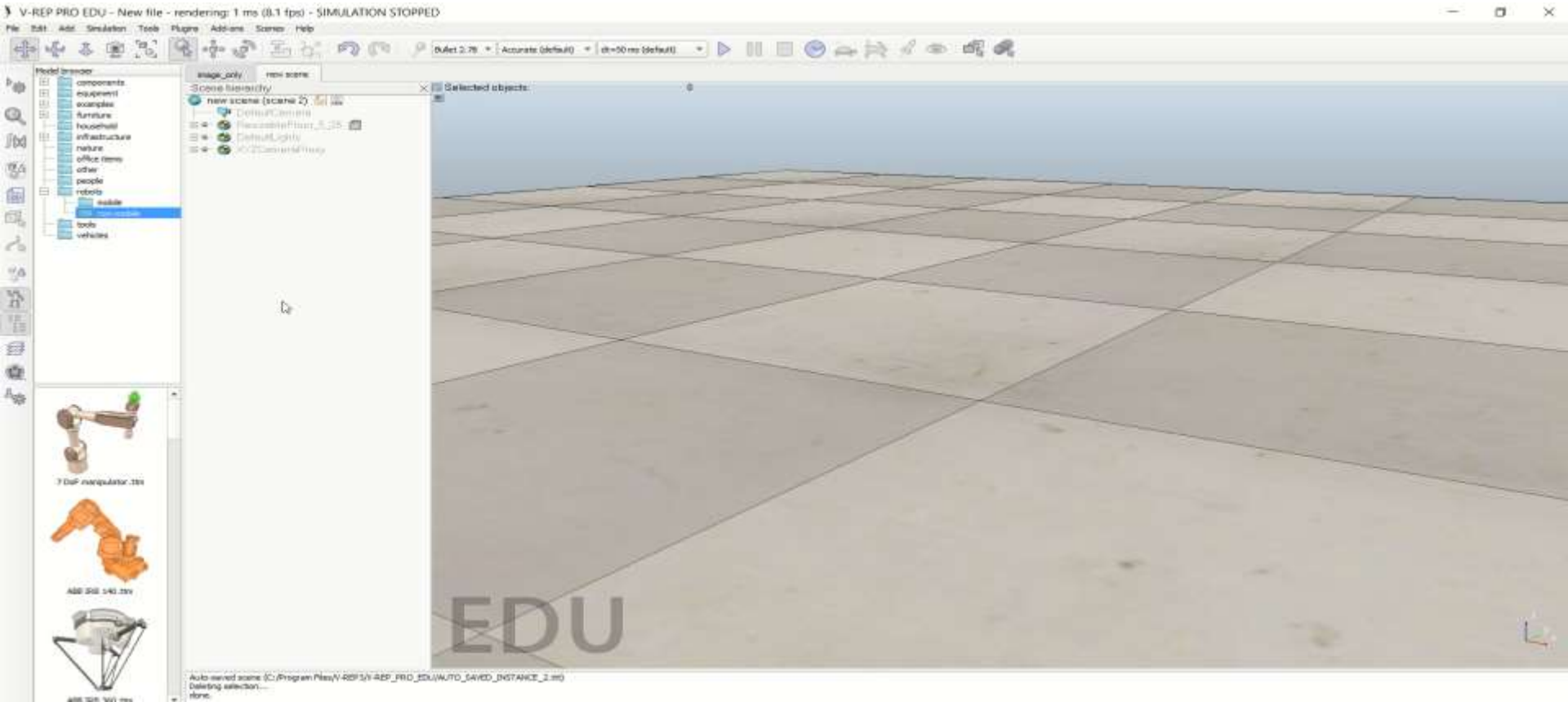
11:26 PM
10/29/2018

Practice 3: line follower robot

- 1°) create new project in VS
- 2°) configure Visual Studio with OpenCV and V-REP API
- 3°) access kinect image by external API
- 4°) in V-REP add a path to follow
- 5°) Is the path visible by the vision sensor? If yes, follow the line!

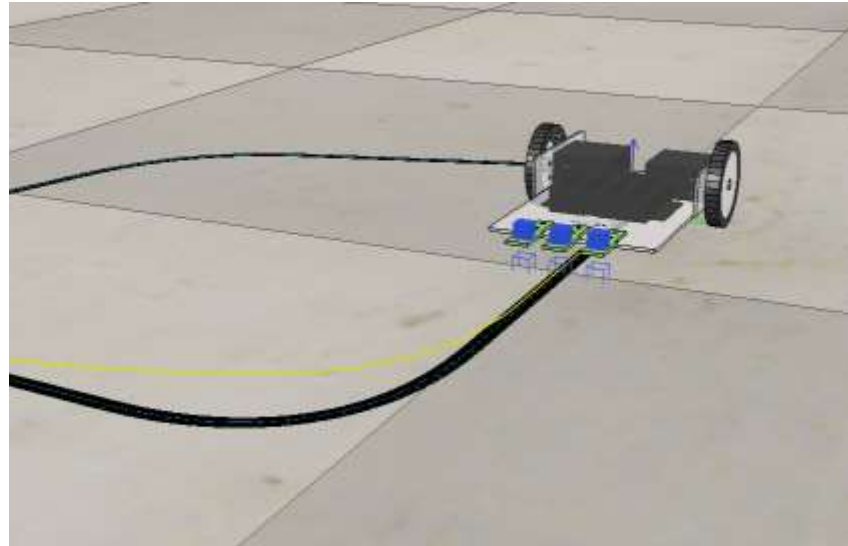
Practice 3: line follower robot

- Drawing the path:



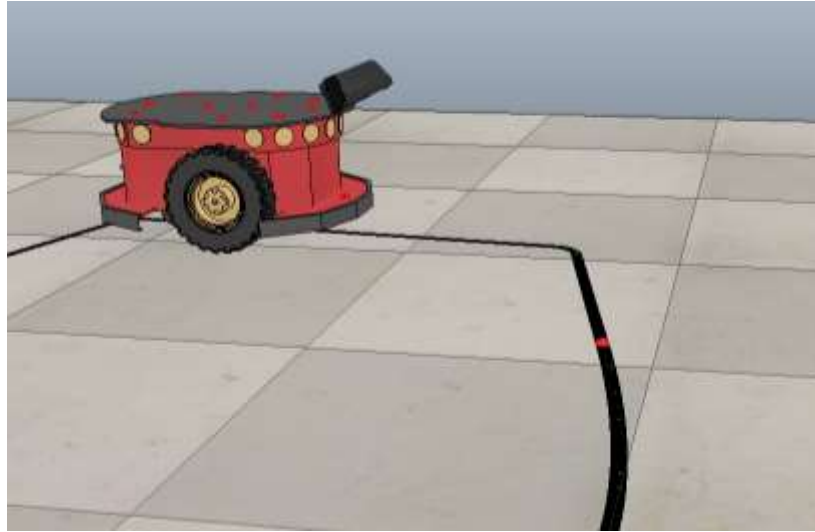
Practice 3: line follower robot

- Test your path:



Practice 3: line follower robot

- Goes back to the Pioneer Robot with a kinect camera:



Practice 3: line follower robot

- Remember:

- Kinect ->

```
function sysCall_init()  
    depthCam=sim.getObjectHandle('kinect_depth')  
    depthView=sim.floatingViewAdd(0.9,0.9,0.2,0.2,0)  
    sim.adjustView(depthView,depthCam,64)  
  
    colorCam=sim.getObjectHandle('kinect_rgb')  
    colorView=sim.floatingViewAdd(0.69,0.9,0.2,0.2,0)  
    sim.adjustView(colorView,colorCam,64)  
end
```

- Pioneer ->

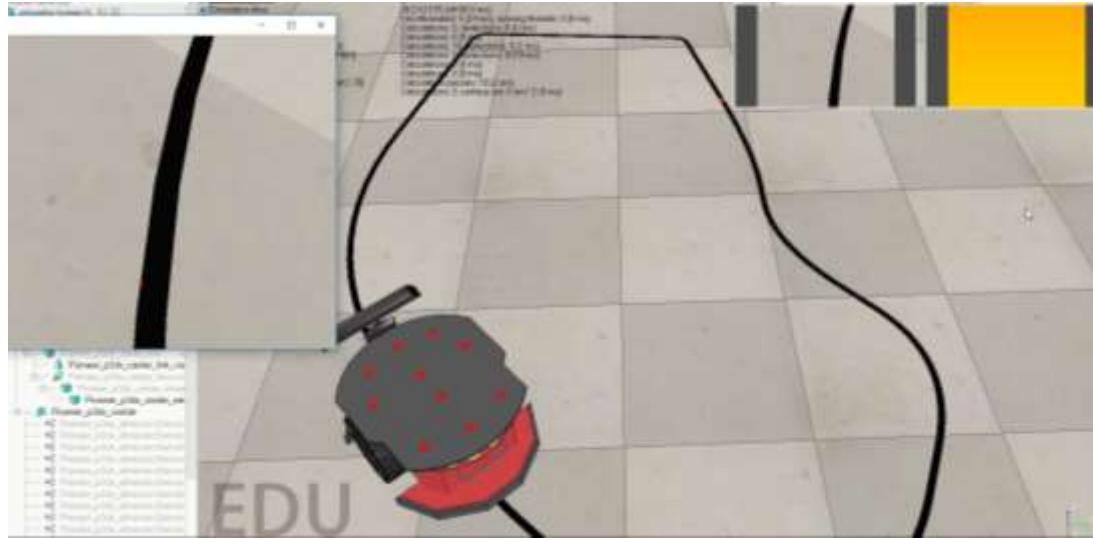
```
function sysCall_init()  
    motorLeft=sim.getObjectHandle("Pioneer_p3dx_leftMotor")  
    motorRight=sim.getObjectHandle("Pioneer_p3dx_rightMotor")  
    vLeft =0;  
    vRight=0;  
    sim.setJointTargetVelocity(motorLeft,vLeft)  
    sim.setJointTargetVelocity(motorRight,vRight)  
end
```

Practice 3: line follower robot

- **Going to Visual Studio**

Practice 3: line follower robot

- Output



Practice 4: controlling Pioneer Robot through keyboard

1°) create new project in VS

2°) configure Visual Studio with OpenCV and V-REP API

3°) access kinect image by external API

4°) code the Pioneer to read commands send by VS

5°) code VS to send commands

6°) control the Pioneer through the keyboard, where "w" goes forward, "s" goes back, "d" goes to the right and "a" goes to the left

Practice 4: controlling Pionner Robot through keyboard

Embedded script

```
1 function sysCall_init()
2     leftMotor=sim.getObjectHandle("Pioneer_3dx_leftMotor")
3     rightMotor=sim.getObjectHandle("Pioneer_3dx_rightMotor")
4     leftSpeed = 0
5     rightSpeed = 0
6     speed = 2
7 -end
8 function sysCall_actuation()
9
10     signalValue=sim.getIntegerSignal("keyboard")
11     print(signalValue)
12     if (signalValue==2018) then
13         leftSpeed = -speed;
14         rightSpeed = -speed;
15     elseif (signalValue==2019) then
16         leftSpeed = speed;
17         rightSpeed = speed;
18     elseif (signalValue==2020) then
19         leftSpeed = -speed;
20         rightSpeed = speed;
21     elseif (signalValue==2021) then
22         leftSpeed = speed;
23         rightSpeed = -speed;
24     else
25         leftSpeed = 0;
26         rightSpeed = 0;
27     end
28     sim.setJointTargetVelocity(leftMotor, leftSpeed)
29     sim.setJointTargetVelocity(rightMotor, rightSpeed)
30 -end
```

Practice 4: controlling Pioneer Robot through keyboard

- **Going to Visual Studio**

Helpful links

- **V-REP manual:**

<http://www.coppeliarobotics.com/helpFiles/>

- **Remote API functions (C/C++):**

<http://www.coppeliarobotics.com/helpFiles/en/remoteApiFunctions.htm>