

統合ロボットシミュレータ



CHOREONOID

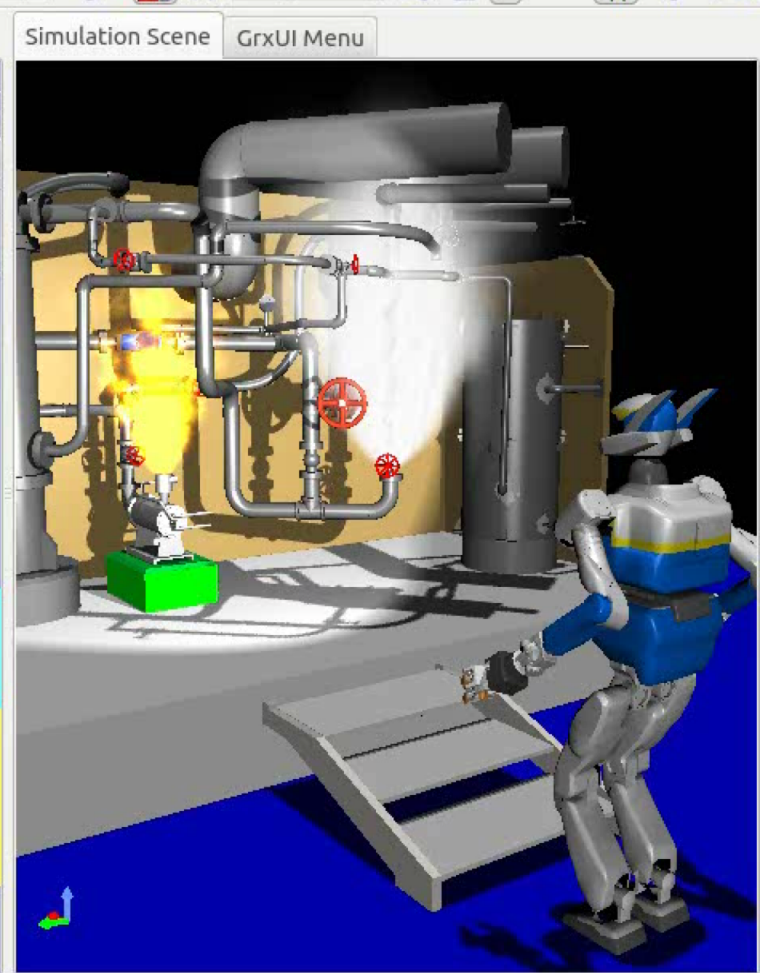
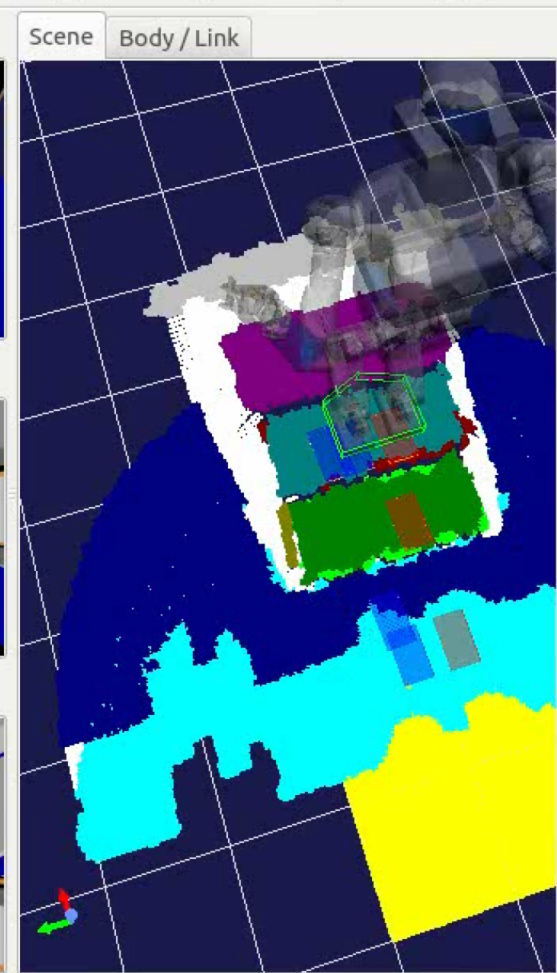
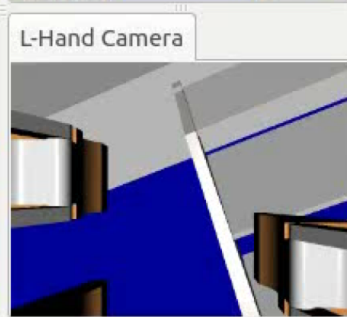
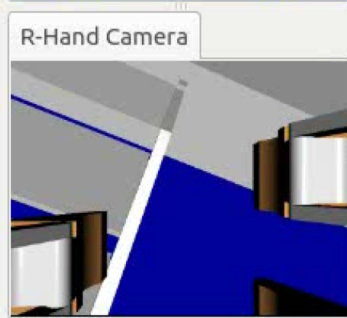
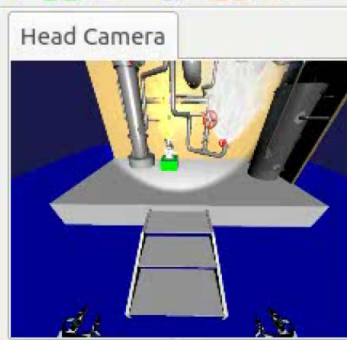
コレオノイド

産業技術総合研究所

中岡 慎一郎

- Items
- ☒ RemoteWorld
 - ☐ HRP2KAI
 - ☒ DRCUse...
 - ☒ Trajec...
 - ☐ Body ...
 - ☐ Point...
 - ☒ Heigh...
 - ☐ OGMap
 - ☐ extra...
 - ☐ Manip...
 - ☐ Gen...
 - ☐ gat...
 - ☐ g...
 - ☐ Objec...
 - ☐ ValveTask...
 - ☐ iREXBalan...
 - ☒ ModelLoader
 - ☐ Simulation...

Property Planne



Task

Balance beam

< Cancel 3 / 6 V Auto >

Set the walk destination

Destination marker Execute the walk and finish Execute the walk

clear emergency state re-measure

+margin -margin +distance2 -distance2 diamond octagon

clearOGM enableOGM disableOGM

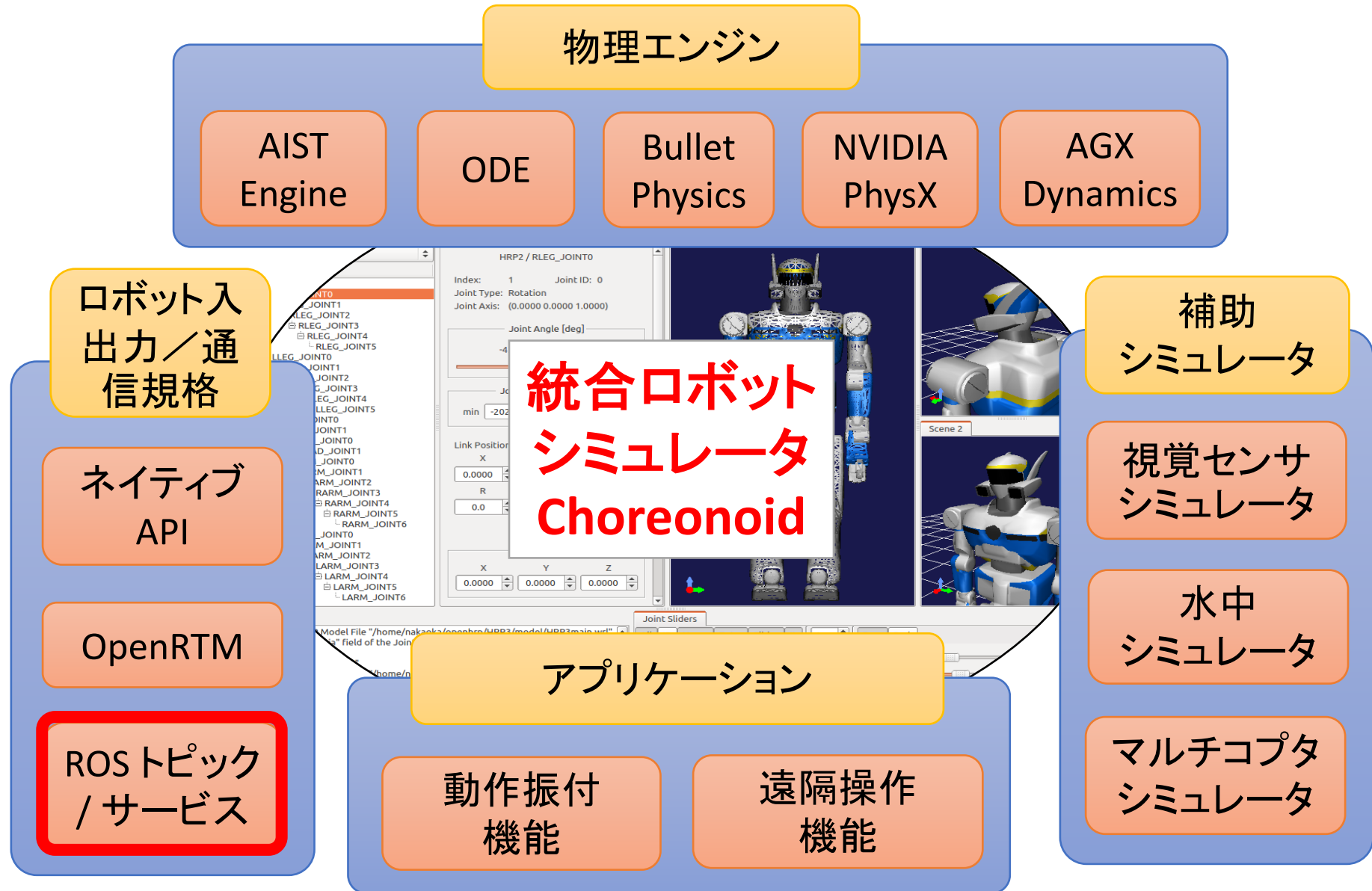
enableCrossStep disableCrossStep

Message DRC Control

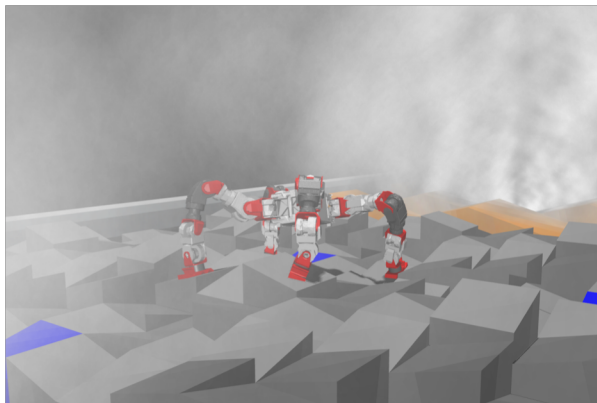
```

1
0
0
waist pitch joint is not protected
waist yaw joint is already protected
configuration-constraint :set-joint-mask-by-groups RLE
G LLEG
configuration-constraint :set-joint-mask-by-groups RLE
G LLEG
    
```

Choreonoidの高機能・高拡張性構造



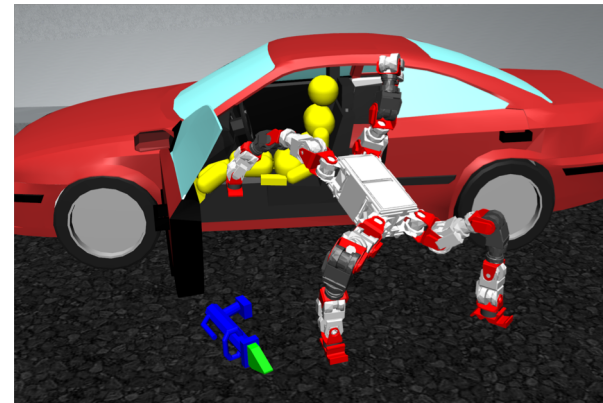
Task T1
Traversing Obstacles



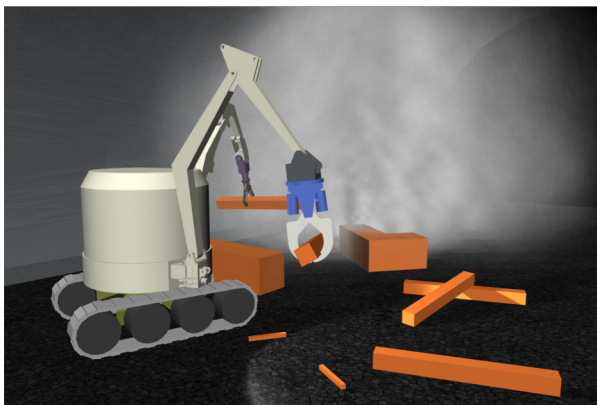
Task T2
Vehicle Inspection



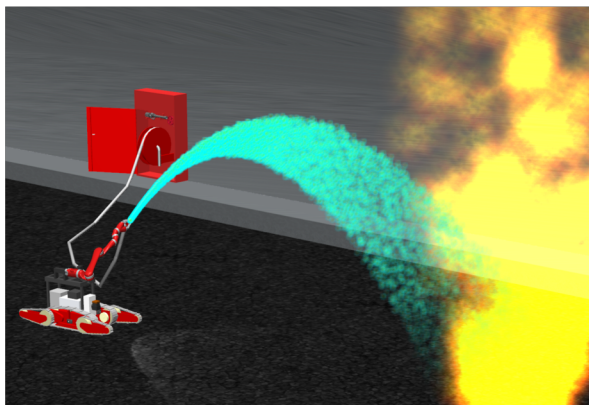
Task T3
Rescue using Tools



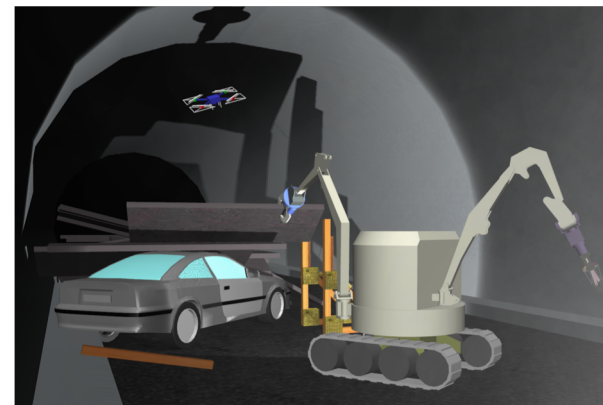
Task T4
Secure the Route



Task T5
Fire Extinguish



Task T6
Shoring and Breaching



Choreonoidの情報

- 公式サイト
 - <http://choreonoid.org>
- ソースコード
 - <https://github.com/s-nakaoka/choreonoid>
- ライセンス
 - MITライセンス