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rotating_cuboid

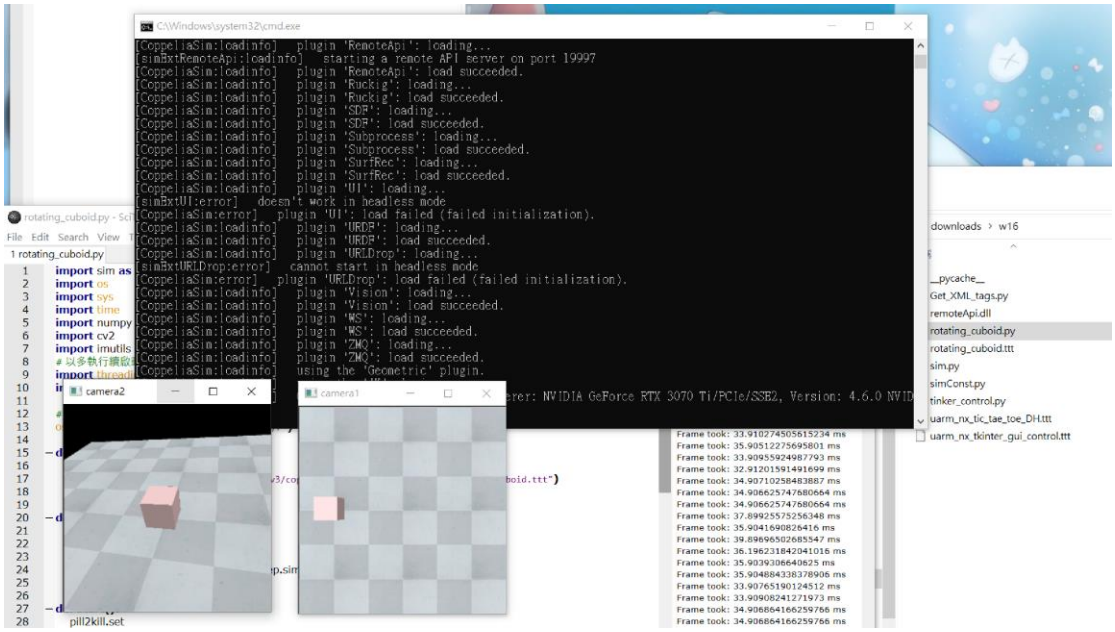
首先要把綠色框起來的地方改成自己 coppeliasim 的位置

```
File  Edit  Search  View  Tools  Options  Language  Buffers  Help
1 rotating_cuboid.py
1   import sim as vrep                  #V-rep library
2   import os
3   import sys
4   import time                 #used to keep track of time
5   import numpy as np          #array library
6   import cv2
7   import imutils
8   # 以多執行續啟動 coppeliasim headless mode
9   import threading
10  import keyboard
11
12  # kill previous coppeliaSim
13  os.system("taskkill /IM coppeliaSim.exe /F")
14
15  def start_copsim():
16      dir = os.getcwd()
17      os.system("Y:/CoppeliaSimEdu_4.3.0_rev3/coppeliaSim.exe -h " + dir + "/rotating_cuboid.ttt")
18      return 'start copsim'
19
20  def pause_copsim():
21      # 暫停執行緒                                    +
22      pill2kill.clear()
23      # 暫停模擬
24      vrep.simxPauseSimulation(clientID, vrep.simx_opmode_oneshot_wait)
25      return "pause copsim"
26
27  def start():
28      pill2kill.set
29      #啟動模擬
30      vrep.simxStartSimulation(clientID, vrep.simx_opmode_oneshot)
31      return "start simulation"
32
33  # 開啟 rotating_cuboid 場景
```

```
>pythonw -u "rotating_cuboid.py"
Setting up the camera system...
Camera setup successful.
Frame took: 35.410404205322266 r
Frame took: 36.087751388549805 r
Frame took: 34.90567207336426 m
Frame took: 34.90638732910156 m
Frame took: 34.90567207336426 m
Frame took: 34.90567207336426 m
Frame took: 39.16335105895996 m
Frame took: 34.905195236206055 r
Frame took: 34.905195236206055 r
Frame took: 34.90567207336426 m
Frame took: 35.9039306640625 ms
Frame took: 35.9041690826416 ms
Frame took: 34.906625747680664 r
Frame took: 35.904884338378906 r
Frame took: 34.90591049194336 m
Frame took: 37.899017333984375 r
Frame took: 34.90591049194336 m
Frame took: 37.897348403930664 r
Frame took: 34.90638732910156 m
Frame took: 35.903215408325195 r
Frame took: 34.90591049194336 m
Frame took: 34.906625747680664 r
Frame took: 35.9039306640625 ms
Frame took: 35.9041690826416 ms
Frame took: 34.90614891052246 m
Frame took: 34.90757942199707 m
Frame took: 35.90273857116699 m
Frame took: 34.90638732910156 m
Frame took: 35.9034538269043 ms
Frame took: 35.9039306640625 ms
Frame took: 36.90052032470703 m
Frame took: 34.458160400390625 r
Frame took: 33.90860557556152 m
Frame took: 35.903215408325195 r
```

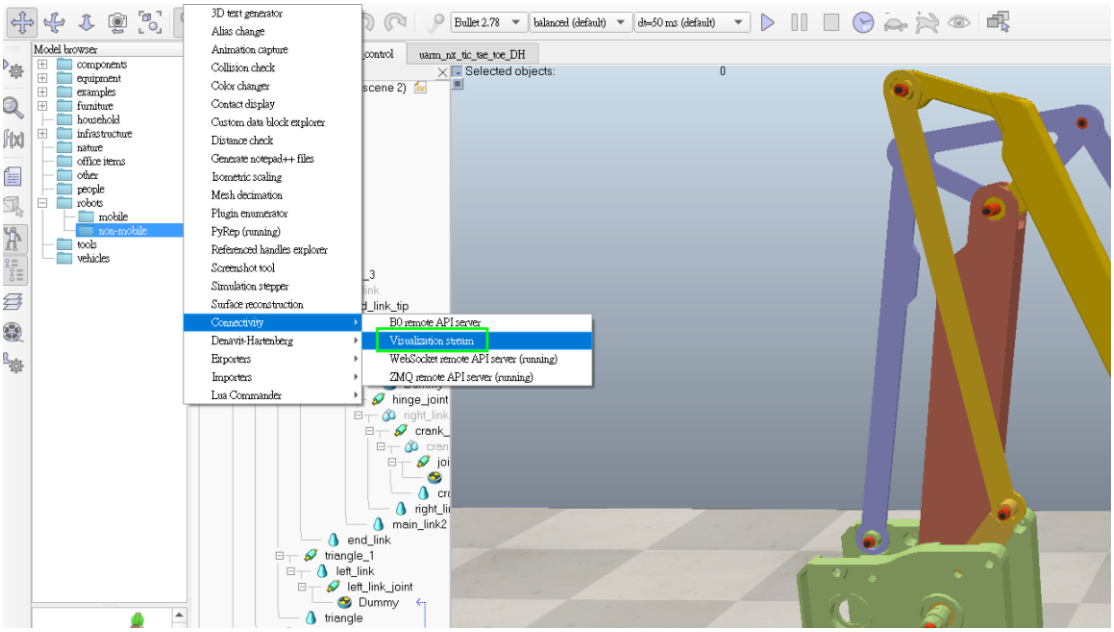
再來就可以 Tools Go

就會跑出兩個攝影機



uarm_nx_tkinter_gui_control

先開啟視覺串流伺服器



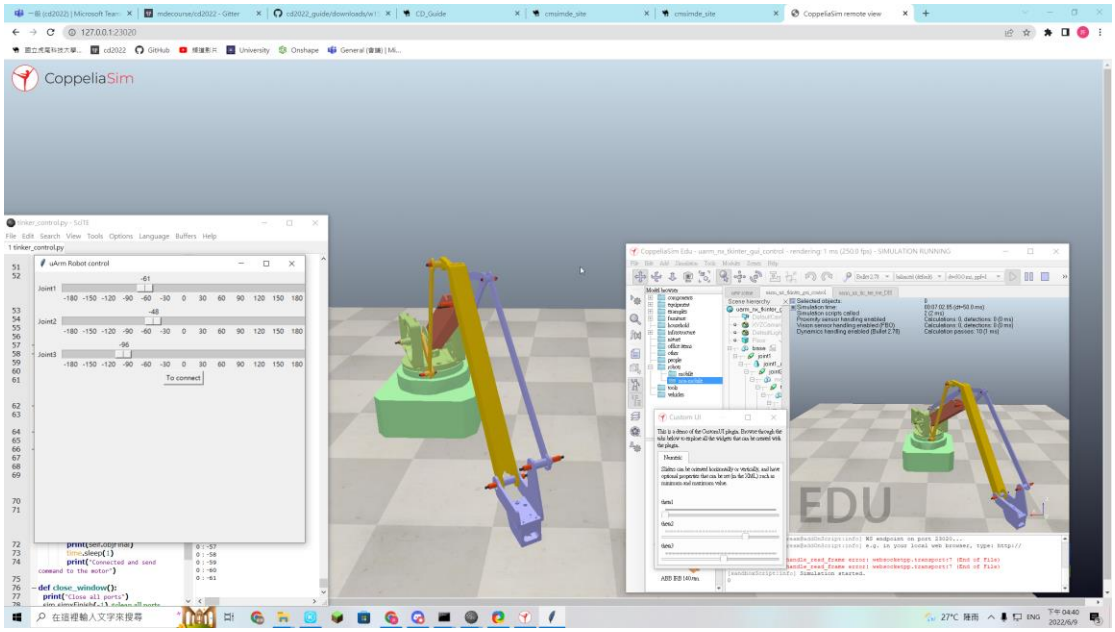
要先開啟 coppeliasim 的模擬

再 Tools Go

再按 to connect

就可以試試看移動 UI 介面

網站上的會跟軟體內的同步


CoppeliaSim
uArm Robot control
Joint1
Joint2
Joint3
To connect
EDU