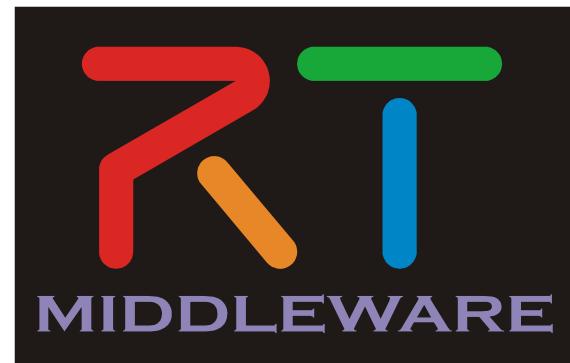


Introduction to RT Component Creation

Nobuhiko Miyamoto

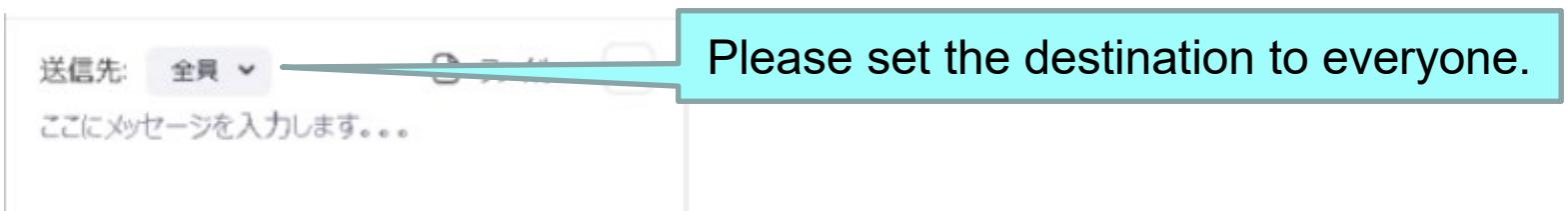
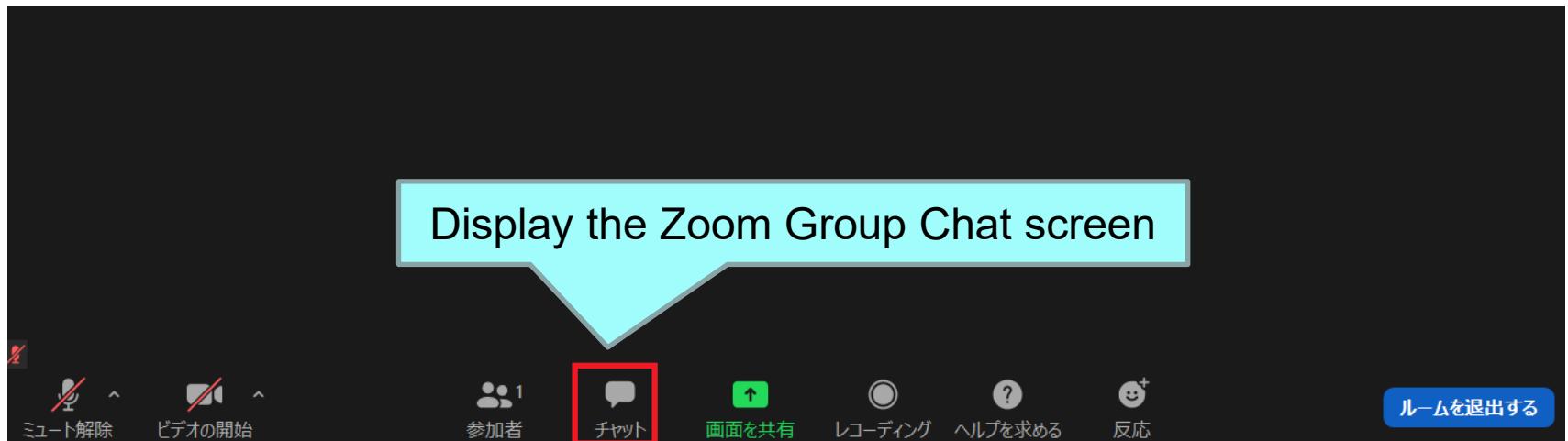
National Institute of Advanced Industrial Science
and Technology

Industrial Cyber-Physical Systems Research Center
Software Platform Research Team



If you have any questions

- Ask a question in Zoom's chat.



- If the problem is not solved by chat, we will provide individual support.

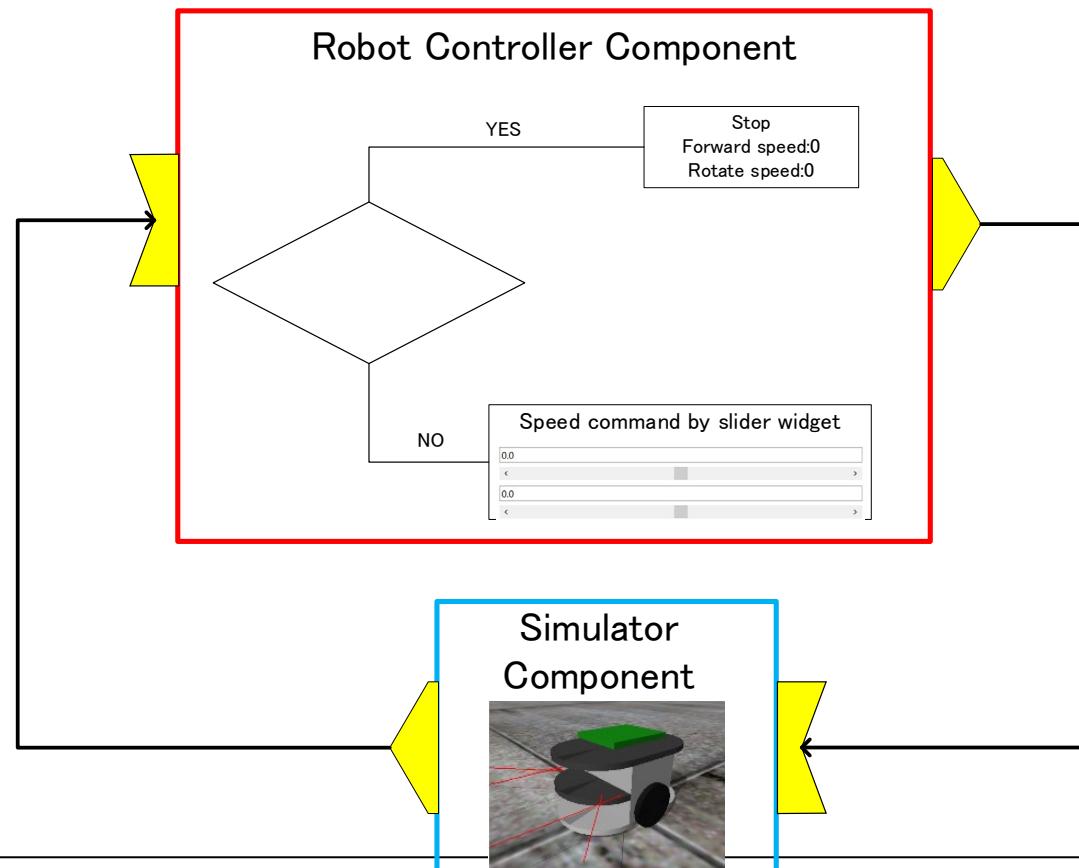
Document

- Please, open the following WEB site.
- Windows
 - https://openrtm.org/openrtm/ja/doc/casestudy/raspberrypi_mouse/raspimouse_tutorial_rtm_seminar/tutorial_rtm_seminar_win_part2
- Ubuntu
 - https://openrtm.org/openrtm/ja/doc/casestudy/raspberrypi_mouse/raspimouse_tutorial_rtm_seminar/tutorial_rtm_seminar_ubuntu_part2



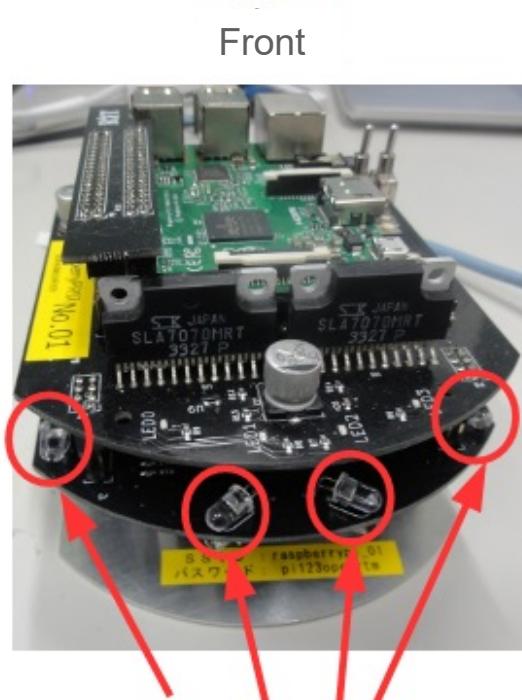
Outline of the training

- Creating component to operate the mobile robot (Raspberry Pi Mouse) on the simulator.
 - Target speed input by GUI
 - Stops when the sensor value exceeds a certain level



Raspberry Pi Mouse Overview

- Raspberry Pi Mouse is an two-wheel drive mobile robot sold by RT.



Front

Distance sensor



Back

Drive wheels

The procedure of the training

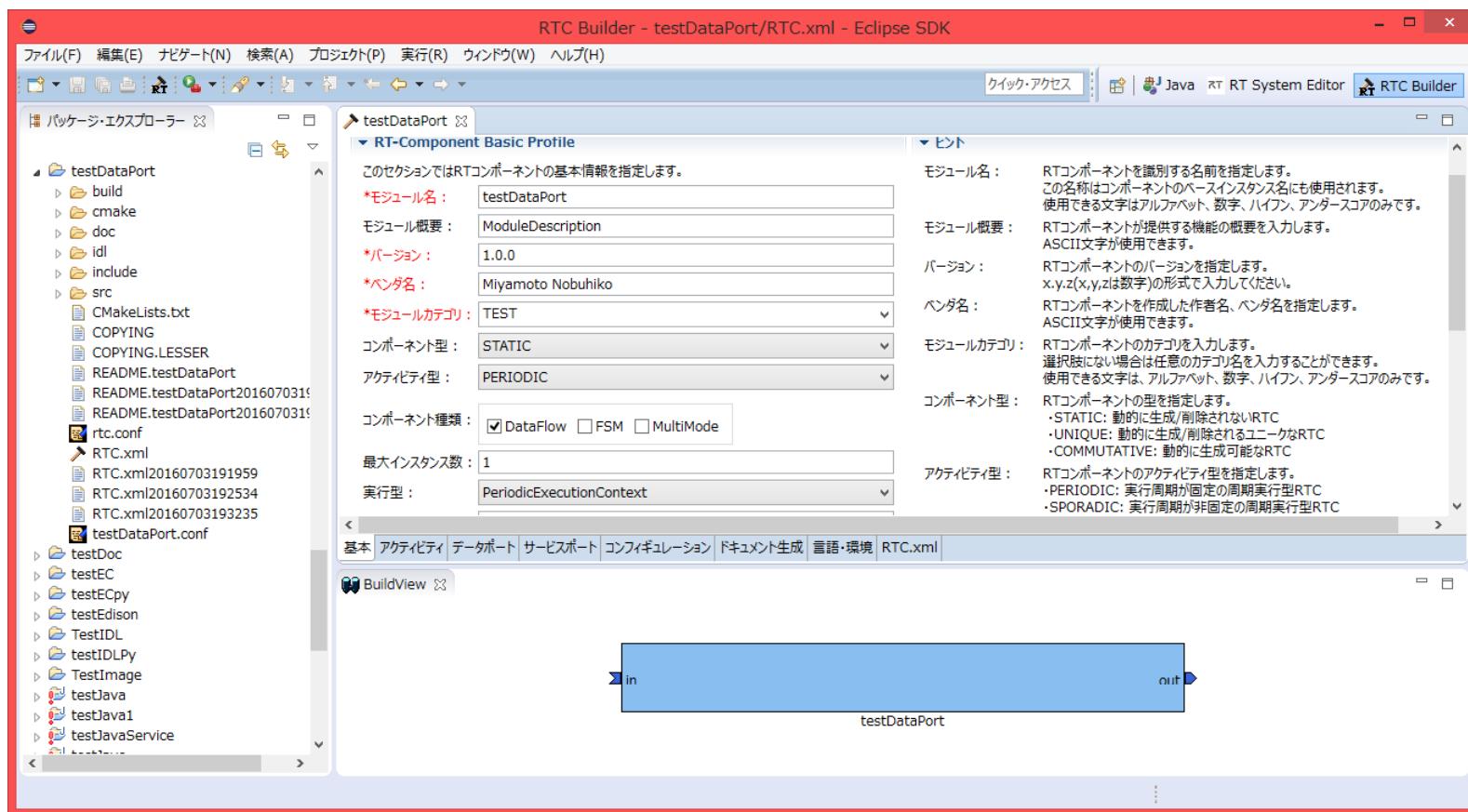
- Creating a template for source code using RTC Builder
- Edit source code and build.
 - Generate various files required for build
 - Various files generated by CMake
 - Editing source code
 - Editing RobotController.h and RobotController.cpp
 - Build
 - Visual Studio, Code::Blocks
- RT System creation and operation check using RT System Editor
 - RT system creation
 - Data port connection, configuration parameter settings.

Component development tools

RTC Builder

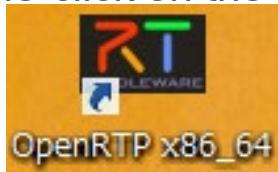
RTC Builder

- A tool that enters component profile information and generates a template such as source code
 - Output C++, Python, Java, Lua source code



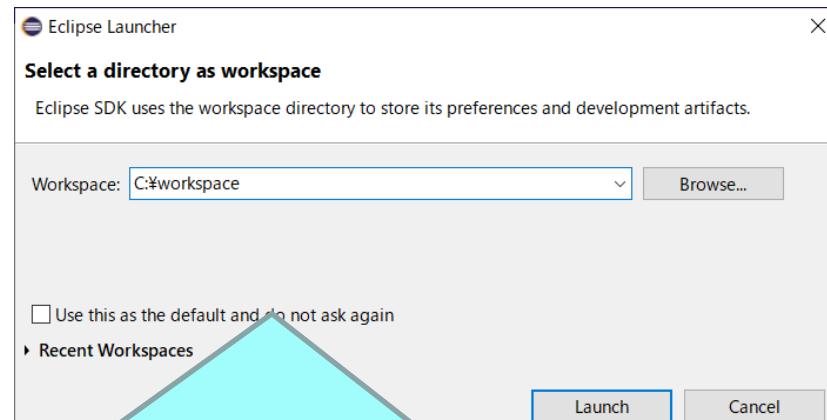
Launch RTC Builder

- Steps to start RTC Builder
 - Windows(OpenRTM-aist 1.2)
 - Double-click on the desktop shortcut



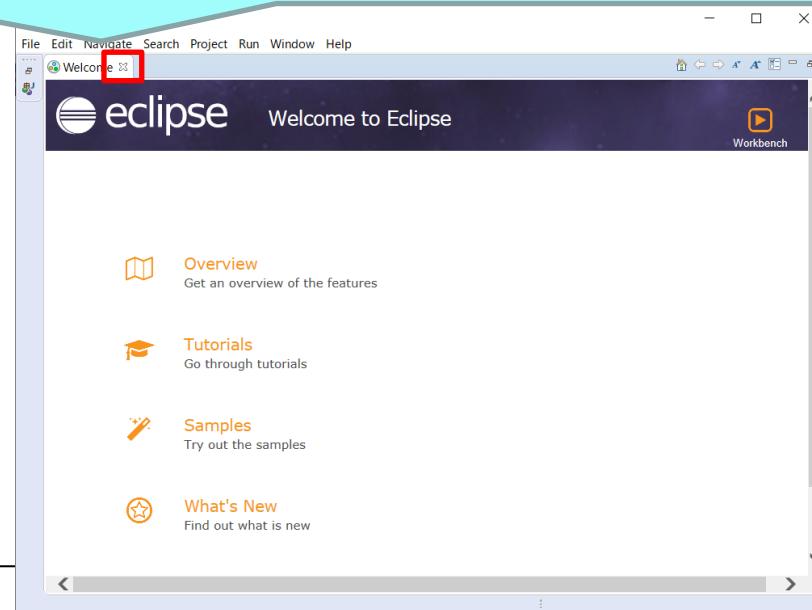
- Ubuntu
 - Enter the following command
 - \$ openrtp

Start RTC Builder

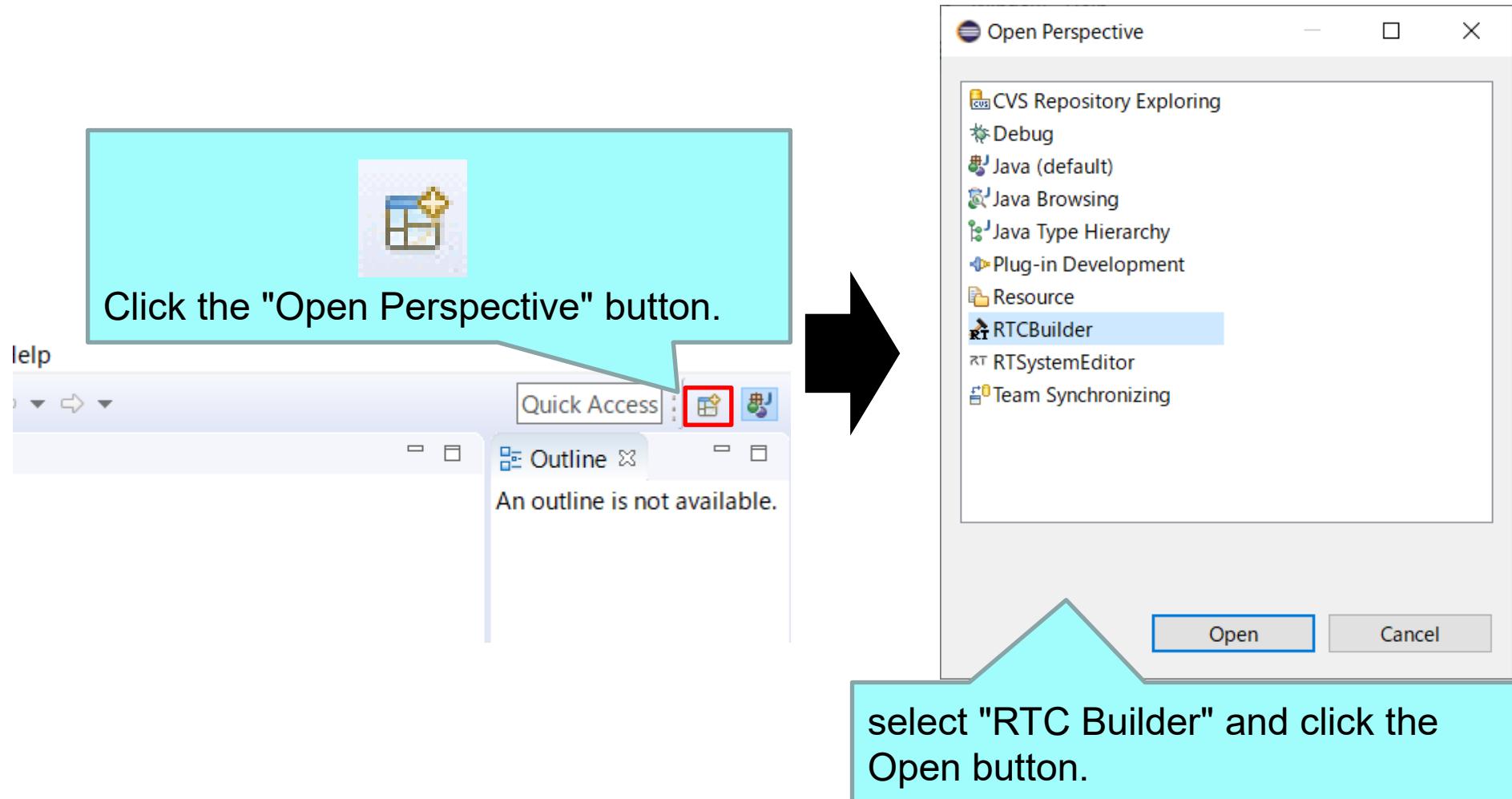


Set any location in the workspace and click Launch.

The Welcome page opens when you first start OpenRTP, so close it.

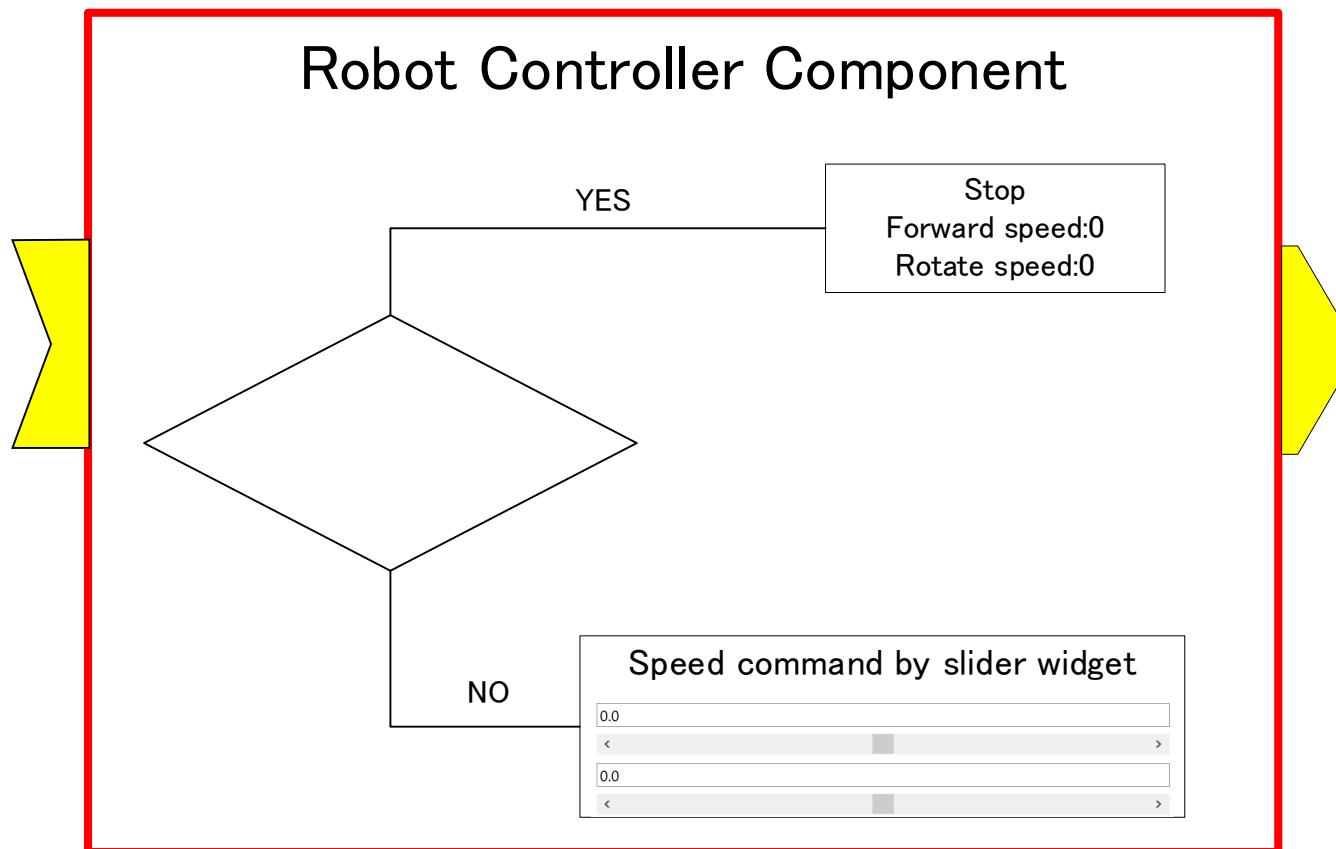


Start RTC Builder

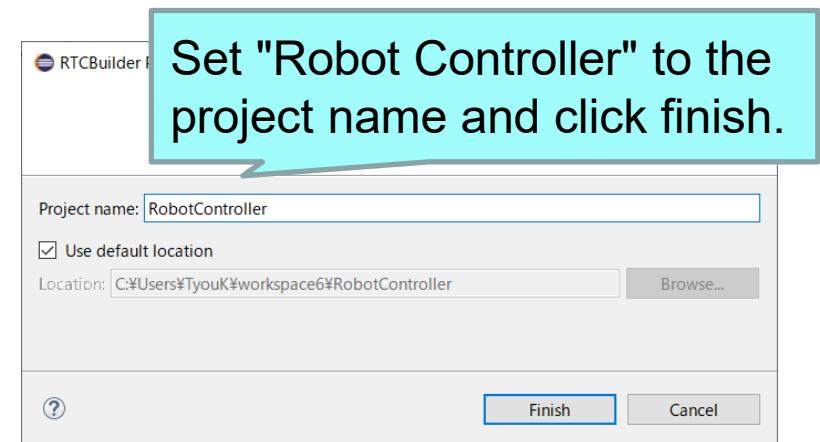
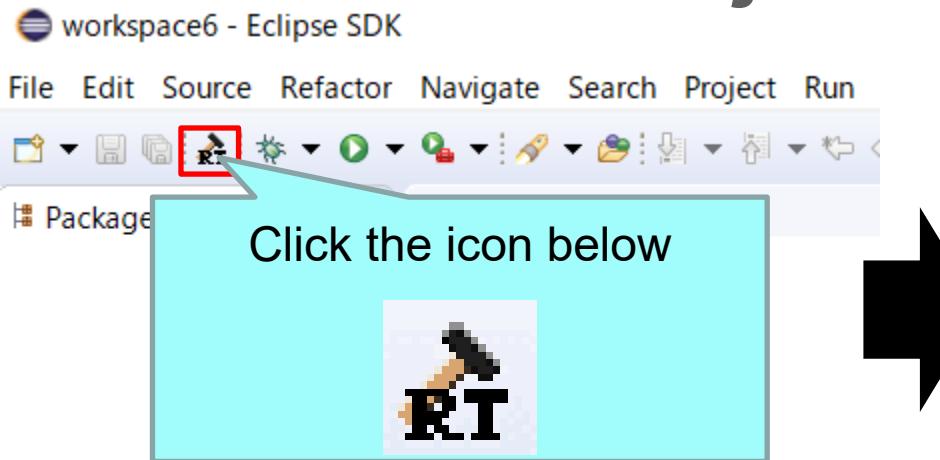


Project creation

- Create skeleton code for the RobotController component.
 - Wheel type mobile robot operation component
 - Operate the robot with GUI
 - Stops when the sensor value exceeds a certain level



Project creation



- A folder called "RobotController" is created in the directory specified in the workspace when Eclipse starts.
 - At this point, only "RTC.xml" and ".project" are generated
- The following items will be set
 - Basic profile
 - Activity profile
 - Data port profile
 - Service port profile
 - configuration
 - document
 - Language environment
 - RTC.xml

Enter basic profile

- Set basic component information such as RT component profile information.
- Code generation, import/export, packaging process

*RobotController X

Basic

RTC profile editor
Enter each item here

This section defines RT-Component Basic information.

*Component name : RobotController

Description : ModuleDescription

*Version : 1.0.0

*Vendor : VenderName

*Category : Category

Component type : STATIC

Component's activity type : PERIODIC

Component kind : DataFlow ESM MultiMode Choreonoid

Hint

Component name : Specifies the component name to This name will also be used as the base instance name of the component. Only alphabet, number, hyphen and underscore are available.

Description : Specifies summary of functions that can be performed by the component. ASCII is available.

Version : Specifies the RT-Component version. Please specify in x.y.z format (x,y,z).

Vendor : Specifies the RT-Component developer or manufacturer. ASCII is available.

Category : Specifies RT-Component category. If it is not one of the selections, another category can be specified. Only alphabet, number, hyphen and underscore are available.

Basic Activity Data Ports Service Ports Configuration Documentation Language and Environment RTC.xml

Select the Basic tab.

RobotController

Enter basic profile

- Component name
 - RobotController
- Module overview
 - Optional (Robot Controller Component)
- version
 - Optional (1.0.0)
- Vendor name
 - Any
- Module category
 - Optional (Controller)
- Component type
 - STATIC
- Activity type
 - PERIODIC
- Component type
 - DataFlow
- Maximum number of instances
 - 1
- Execution type
 - PeriodicExecutionContext
- Execution cycle
 - 1000.0
- Overview
 - Any

Basic

▼ RT-Component Basic Profile

This section defines RT-Component Basic information.

| | |
|------------------------------|--|
| *Component name : | RobotController |
| Description : | ModuleDescription |
| *Version : | 1.0.0 |
| *Vendor : | VenderName |
| *Category : | Category |
| Component type : | STATIC |
| Component's activity type : | PERIODIC |
| Component kind : | <input checked="" type="checkbox"/> DataFlow <input type="checkbox"/> FSM <input type="checkbox"/> MultiMode <input type="checkbox"/> Choreonoid |
| Number of maximum instance : | 1 |
| Execution type : | PeriodicExecutionContext |
| Execution rate : | 1000.0 |
| Abstract : | |
| RTC Type : | |

Activity settings

- Set the activity to use.

Activity

- Activity

This section specifies the action callback that is used.

| Component Action concerning the component's initialization and finalization | | |
|---|---------------|---------------|
| onInitialize | onFinalize | |
| Component Action concerning the ExecutionContext's startup and shutdown | | |
| onStartup | onShutdown | |
| Component Action in the alive state | | |
| onActivated | onDeactivated | onAborting |
| onError | onReset | |
| Dataflow Component Action | | |
| onExecute | onStateUpdate | onRateChanged |
| FSM Component Action | | |
| onAction | | |
| Mode Component Action | | |

[Basic](#) [Activity](#) [Data Ports](#) [Service Ports](#) [Configuration](#) [Documentation](#) [Language and Environment](#) [RTC.xml](#)

Select the Activity tab.

- Steps to enable specified activity

1. Select the activity name you want to use or not use
(Displayed in red when selected)

| Component Action in the alive state | | |
|-------------------------------------|---------------|---------------|
| onActivated | onDeactivated | onAborting |
| onError | onReset | |
| Dataflow Component Action | | |
| onExecute | onStateUpdate | onRateChanged |
| FSM Component Action | | |
| onAction | | |
| Mode Component Action | | |

2. After selecting the activity name,
select ON-OFF.

Activity name : ON OFF

Activated activity names have a blue background

*RobotController

| Component Action in the alive state | | |
|-------------------------------------|---------------|---------------|
| onStartup | onShutdown | |
| onActivated | onDeactivated | onAborting |
| onError | onReset | |
| Dataflow Component Action | | |
| onExecute | onStateUpdate | onRateChanged |
| FSM Component Action | | |
| onAction | | |
| Mode Component Action | | |
| onModeChanged | | |

Documentation

This section specifies a short description of each action.
If the action above is selected, each document can be described.

Activity name : ON OFF

[Basic](#) [Activity](#) [Data Ports](#) [Service Ports](#) [Configuration](#) [Documentation](#) [Language and Environment](#) [RTC.xml](#)

Activity settings

| コールバック関数 | 処理 |
|---------------|---|
| onInitialize | Initialization process |
| onActivated | Called only once when activated |
| onExecute | Called periodically when active |
| onDeactivated | Called only once when deactivated |
| onAborting | Called only once before entering ERROR state |
| onReset | Called only once when reset |
| onError | Called periodically in ERROR state |
| onFinalize | Called only once at the end |
| onStateUpdate | Called every time after onExecute |
| onRateChanged | Called only once when the ExecutionContext rate changes |
| onStartup | Called only once when ExecutionContext starts execution |
| onShutdown | Called only once when ExecutionContext stops executing |

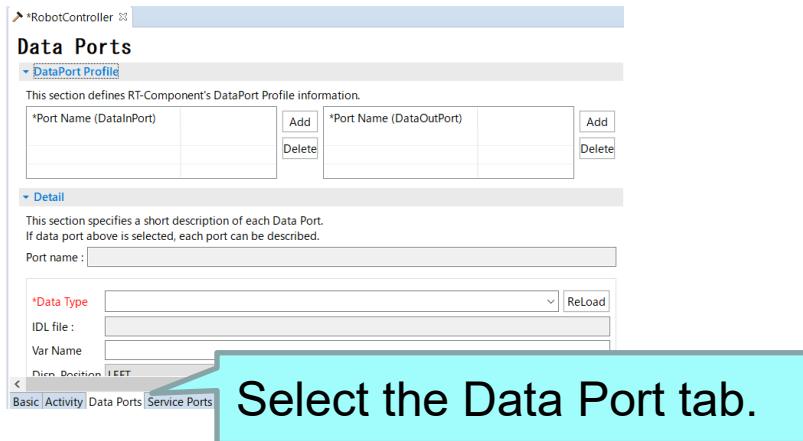
Activity settings

- Enable the following activities
 - onInitialize
 - **onActivated**
 - **onDeactivated**
 - **onExecute**



Data port settings

- Add and set InPort and OutPort



- Steps to add a data port

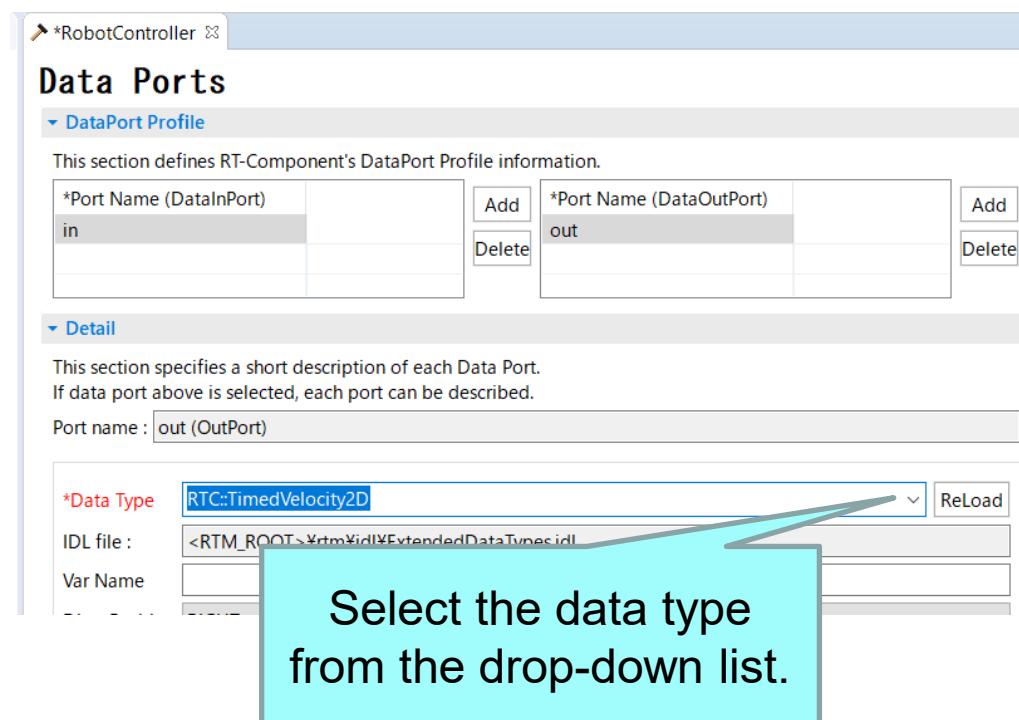
Data Ports

This screenshot continues from the previous one, showing the 'DataPort Profile' tab selected. It displays the 'DataInPort' section where an 'Add' button is highlighted with a red box. A large callout box with a blue border and white text points to this button with the text 'Click the add button for ImPort or OutPort.' To the right, another screenshot shows the 'DataOutPort' section with a similar 'Add' button highlighted, and a callout box pointing to it with the text 'Click the port name to rename it.'

This screenshot shows the 'DataOutPort' section after adding a new port. The 'Port Name (DataOutPort)' field now contains 'in' (InPort). The 'Data Type' dropdown is set to 'RTC-Timed shortSeq', and the 'IDL file' dropdown shows '<RTM.RC>¥rtm¥idl¥BasicDataType.idl'. A callout box with a blue border and white text points to the 'Set each item.' text below the interface.

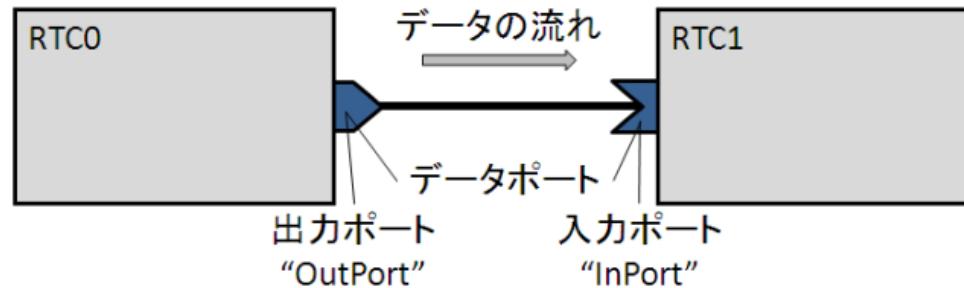
Data port settings

- Set the following InPort
 - **in**
 - Data Type : **RTC::TimedShortSeq**
 - Please do not mistake it for TimedShort type.
- Set the following OutPort
 - **out**
 - Data Type : **RTC::TimedVelocity2D**
 - Please do not mistake it for TimedVelocity3D type and TimedVector2D.

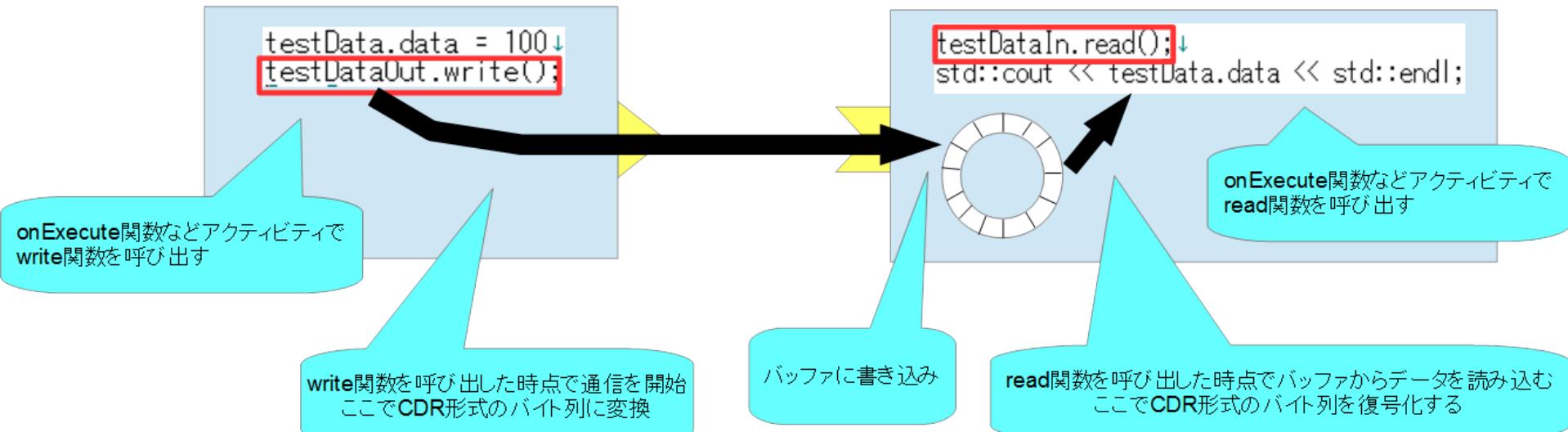


About the data port

- Port for communicating continuous data

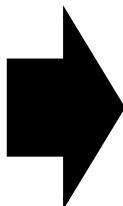


- 以下の例はデータフロー型がpush、サブスクリプション型がflush、インターフェース型がcorba_cdrの場合



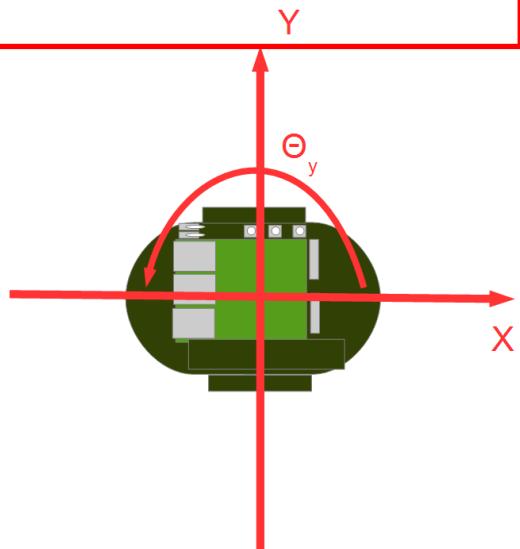
About RTC::TimedVelocity2D type

- Data type for expressing the speed of a mobile robot defined in ExtendedDataTypes.idl.
 - **vx**: Velocity in the X-axis direction
 - **vy**: Velocity in the Y-axis direction (0 assuming the wheels do not skid)
 - **va**: Angular velocity around the Z axis



Set straight speed with vx and rotation speed with va

```
struct Velocity2D {  
    /// Velocity along the x axis in metres per second.  
    double vx;  
    /// Velocity along the y axis in metres per second.  
    double vy;  
    /// Yaw velocity in radians per second.  
    double va;  
};
```



Configuration Parameter settings

- Add and set configuration parameters

RT-Component Configuration Parameter

▼ RT-Component Configuration Parameter Definitions

This section defines RT-Component Configuration Parameter.

| | |
|-------|--------|
| *Name | Add |
| | Delete |

Config.

Parameter

▼ Detail

This section specifies each Configuration Parameter description.

Parameter name :

Data type

*Type

*Default Value

Variable

Variable name :

Default

Basic Activity Data Ports Service Ports Configuration Documentation Language and Environment View Log

Select the Configuration tab.

- Steps to add configuration parameters

RT-Component Configuration Parameter

▼ RT-Component Configuration Parameter Definitions

This section defines RT-Component Configuration Parameter.

*Name

Add

Delete



Click the add button.

RT-Component Configuration Parameter

▼ RT-Component Configuration Parameter Definitions

This section defines RT-Component Configuration Parameter.

| | |
|-------|--------------------------------------|
| *Name | <input type="text" value="speed_x"/> |
|-------|--------------------------------------|

Add

Delete

Click the parameter name to rename it.

▼ Detail

This section specifies each Configuration Parameter description.

Parameter name :

* Set each item.

Configuration Parameter settings

- Set the following configuration parameters
 - **speed_x**
 - Type : double
 - Default Value : 0.0
 - Constraint : $-1.5 < x < 1.5$
 - Widget : slider
 - Step: 0.01
 - **speed_r**
 - Type : double
 - Default Value : 0.0
 - Constraint : $-2.0 < x < 2.0$
 - Widget : slider
 - Step: 0.01

This section defines RT-Component Configuration Parameter.

| | | |
|---------|--|--------|
| *Name | | Add |
| speed_x | | Delete |
| speed_r | | |
| stop_d | | |

▼ Detail

This section specifies each Configuration Parameter description.

Parameter name : speed_x

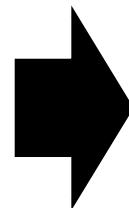
| | |
|-----------------|----------------|
| *Type | double |
| *Default Value | 0.0 |
| Variable name : | |
| Unit : | |
| Constraint : | -1.5 < x < 1.5 |
| Widget : | slider |
| Step : | 0.01 |

Enable operation of mobile robots using GUI (slider)

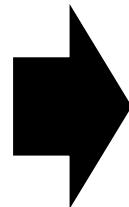
| | | |
|-----|---|---|
| 0.0 | < | > |
| 0.1 | < | > |

Configuration parameter constraints, and widget settings

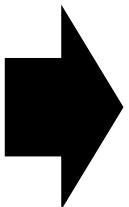
- Show GUI when editing configuration parameters in RT System Editor

A simple text input field containing the number "0".

- Widget:text

A text input field containing the number "40", with up and down arrow buttons on the right side.

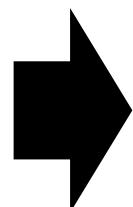
- Constraint: $0 \leq x \leq 100$
- Widget:spin
- Step : 10

A horizontal slider component with a central grey bar and arrows at both ends. The number "40" is displayed in the text input field above it.

- Constraint: $0 \leq x \leq 100$
- Widget:slider
- Step : 10

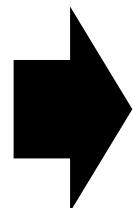
Configuration parameter constraints, and widget settings

- Constraint : (0,1,2,3)
- Widget : radio



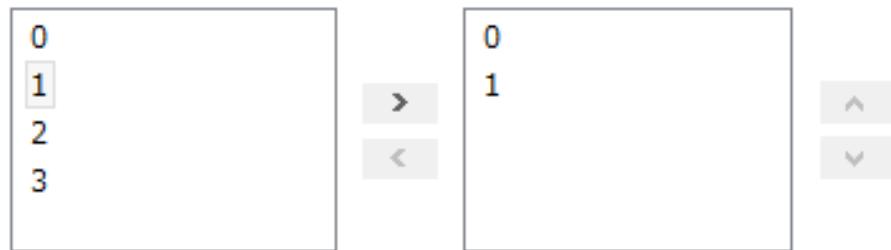
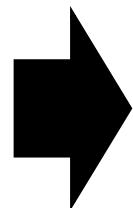
A horizontal row of four radio buttons labeled 0, 1, 2, and 3. Radio button 2 is selected (indicated by a black dot), while others are empty.

- Constraint : (0,1,2,3)
- Widget : checkbox



A horizontal row of three checkboxes labeled 0, 1, and 2. Checkboxes 0 and 2 are checked (indicated by a blue checkmark), while checkbox 1 is empty.

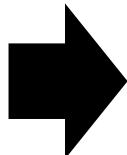
- Constraint : (0,1,2,3)
- Widget : ordered_list



A configuration interface for an ordered list. On the left, a vertical list shows items 0, 1, 2, and 3. To the right, two rectangular boxes show the current order: the first box contains 0 and 1, and the second box contains 0 and 1. Between the boxes are navigation buttons: a double-right arrow, a left arrow, and a right arrow. To the far right are additional up and down arrow buttons.

Configuration Parameter settings

- Set the following configuration parameters
 - stop_d**
 - Type : int
 - Default Value : 30



Stop when the sensor value is greater than or equal to this value

This section defines RT-Component Configuration Parameter.

| *Name | Add |
|---------------|-----|
| speed_x | |
| speed_r | |
| stop_d | |
| | |
| | |
| | |

▼ Detail

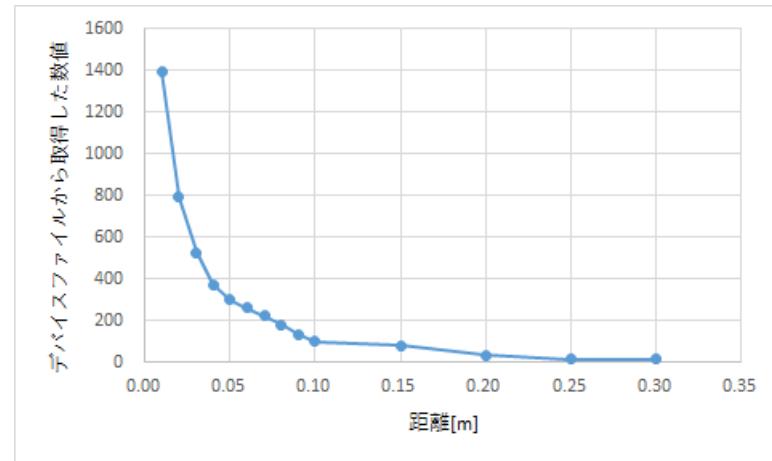
This section specifies each Configuration Parameter description.

Parameter name : stop_d

| | |
|-----------------|------|
| *Type | int |
| *Default Value | 30 |
| Variable name : | |
| Unit : | |
| Constraint : | |
| Widget : | text |
| Step : | |

Raspberry Pi mouse distance sensor

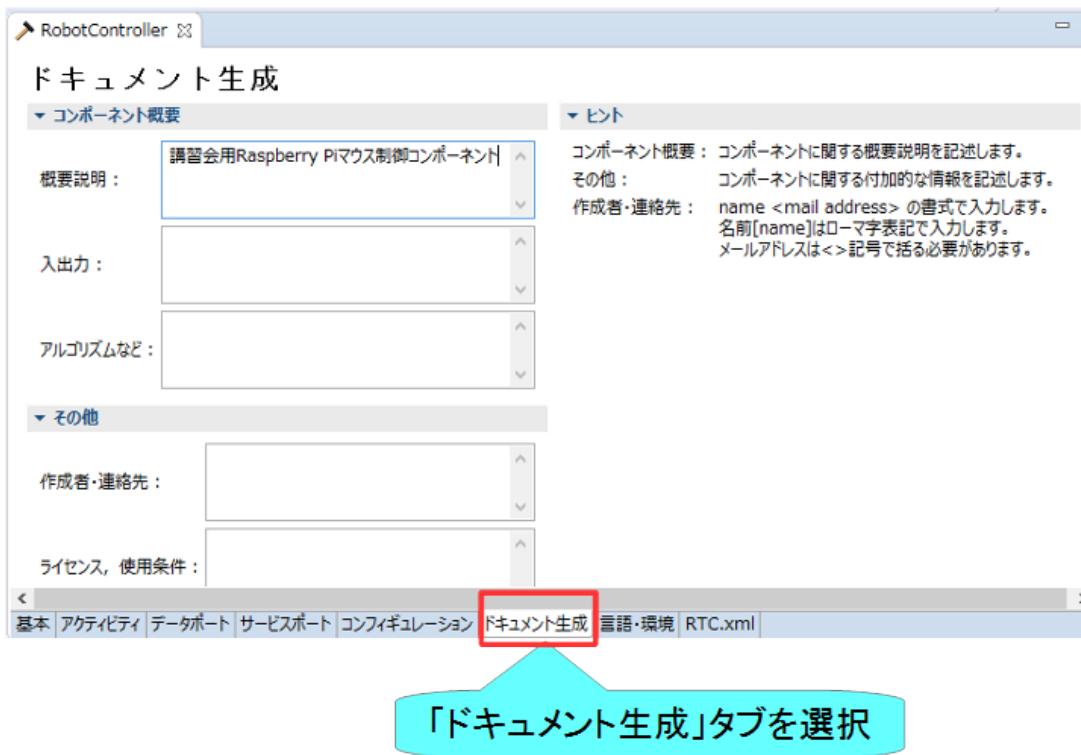
- Raspberry Pi mouse is equipped with a distance sensor
 - The measured value becomes larger as the distance to the object is shorter.



- The simulator also calculates and outputs a value close to this data.

ドキュメントの設定

- 各種ドキュメント情報を設定



- 今回は適当に設定しておいてください。
 - 空白でも大丈夫です

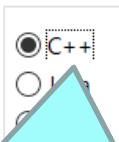
Language setting

- Set information about the language to be implemented and the operating environment.

Language and Environment

Language

This section defines a language that is used.



Hint

Language : Si
Environment : Si
SL
TI
is

Set the language.
This time, set "C ++".

This section defines depending libraries and Oses etc that are used.

| Version | OS | | Add | Delete |
|---------|----|--|-----|--------|
| | | | | |
| | | | | |
| | | | | |

Detail information

| OS Version | |
|------------|--|
| | |

Add

Delete

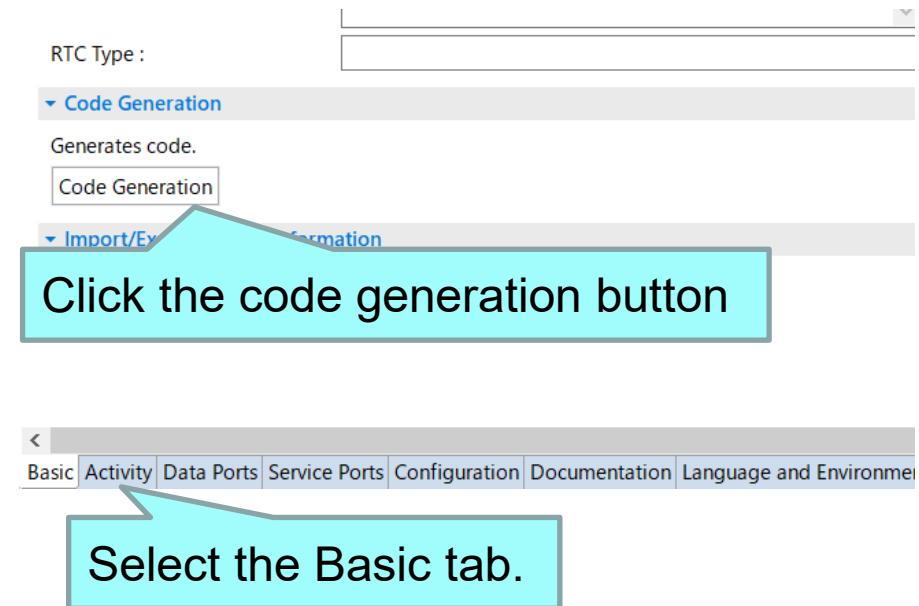
CPU

Select the Language and Environment tab.

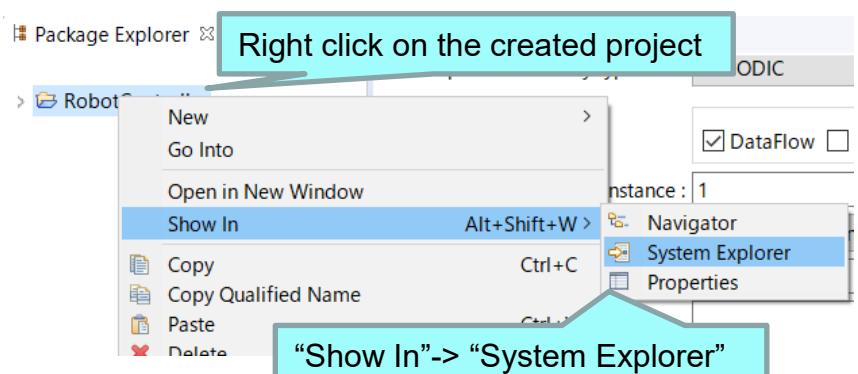
Skeleton code generation

- A skeleton code is generated by pressing the code generation button from the basic tab.

- Workspace¥RobotController
 - Source code
 - C++ Source files(.cpp)
 - Header files (.h)
 - CMakeLists.txt
 - rtc.conf、RobotController.conf
 - etc.



- Check the generated file
 - Right-click the created project and select "Show In"(表示方法)-> "System Explorer".
 - Explorer will open the workspace folder, so check if the above file exists



Edit source code, build RTC

Steps to build

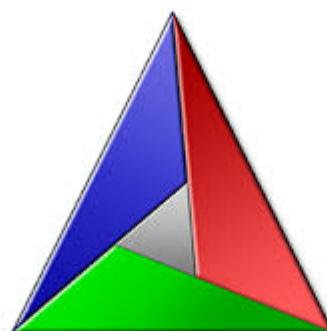
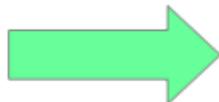
- Generate various files required for build
 - Various files generated by CMake
- Edit the source code
 - Edit RobotController.h
 - Edit RobotController.cpp
- Build
 - Windows: Visual Studio
 - Ubuntu: Code::Blocks

CMake

- Generate various files required for build
 - Describe the settings in CMakeLists.txt.
 - CMakeLists.txt is also generated when you create the skeleton code in RTC Build



CMakeLists.txt



CMake



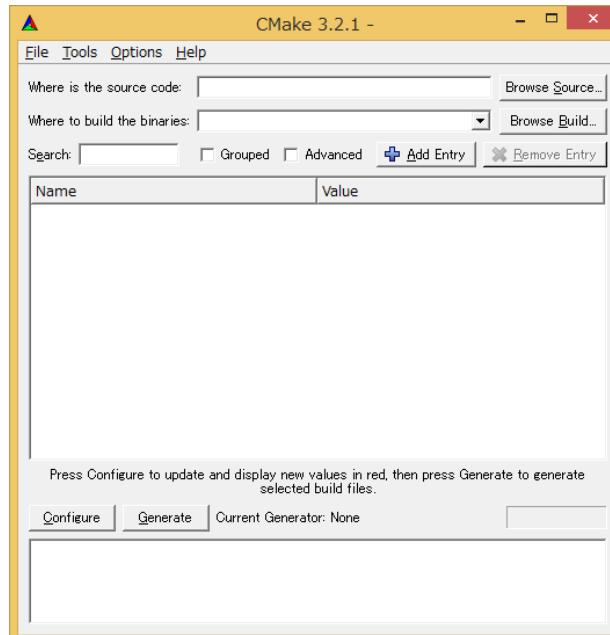
Makefile



Visual Studio
(ソリューションファイル、
プロジェクトファイル等)

Generating files needed for build

- Start CMake
 - Windows 7
 - 「スタート」→「すべてのプログラム」→「CMake」→「CMake (cmake-gui)」
 - Windows 8.1
 - 「スタート」→「アプリビュー(右下矢印)」→「CMake」→「CMake (cmake-gui)」
 - Windows 10
 - 左下の「ここに入力して検索」にCMakeと入力して表示されたCMake(cmake-gui)を起動
 - Ubuntu
 - Enter the following command
 - cmake-gui



cmake-guiの起動

- Windows 8.1



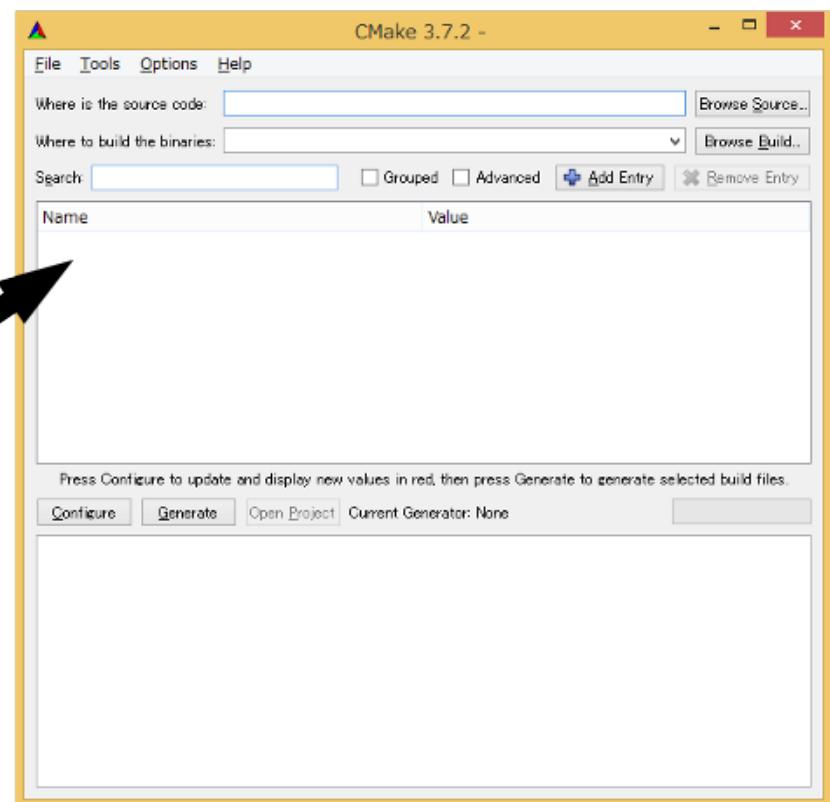
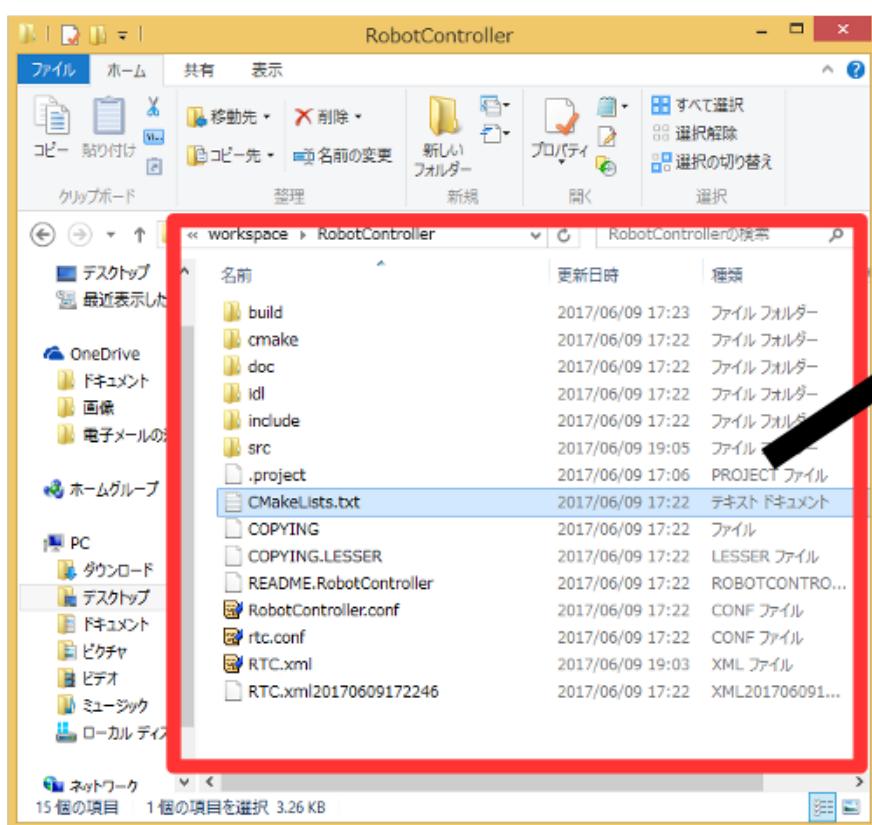
cmake-guiの起動

- Windows 10

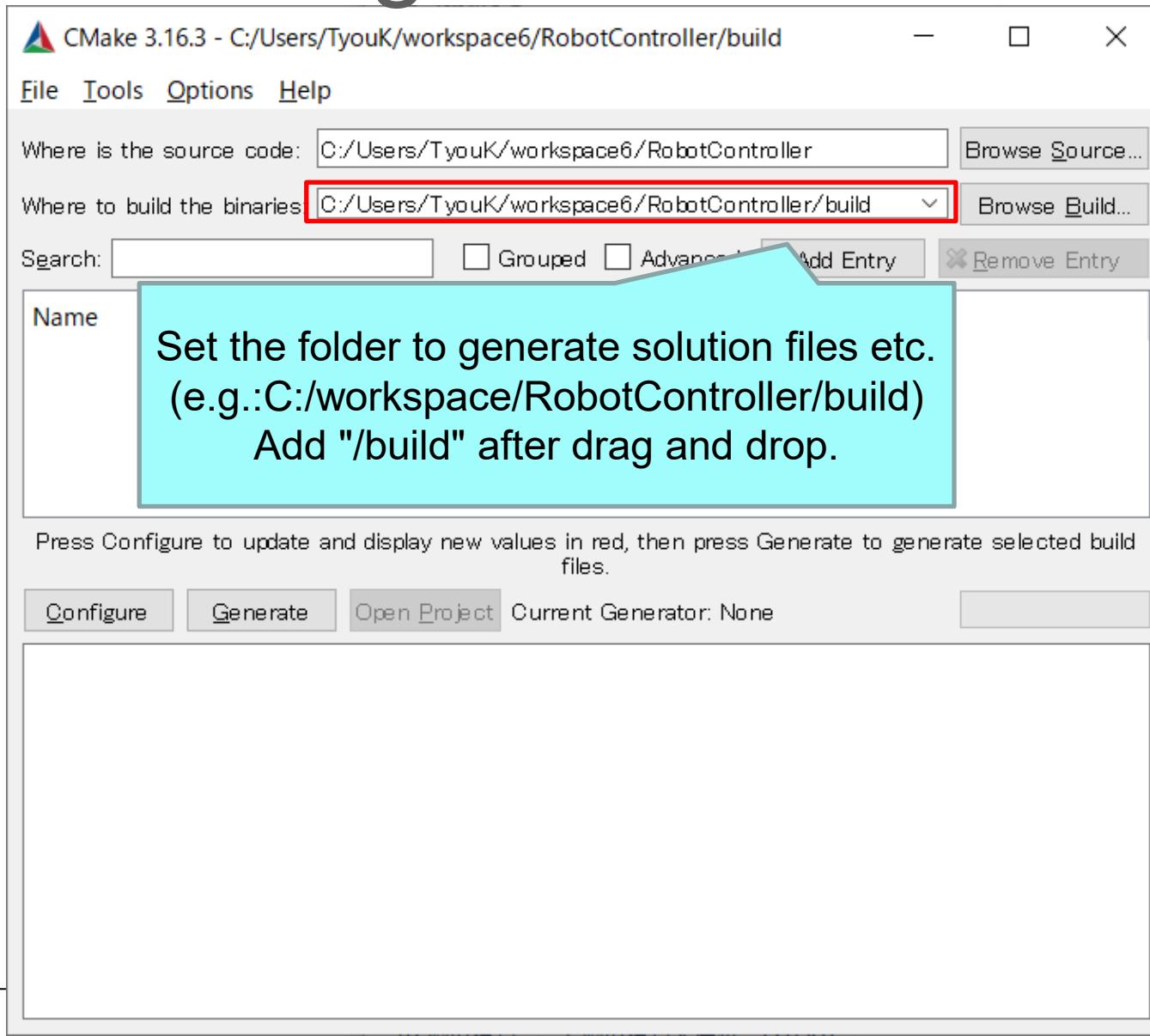


Generating files needed for build

- Drag and drop CMakeLists.txt onto cmake-gui
 - CMakeLists.txt is a folder for projects generated by RTC Builder.
(例：C:\workspace\RobotController)



Generating files needed for build



Press Configure to update and display new values in red, then press Generate to generate selected build files.

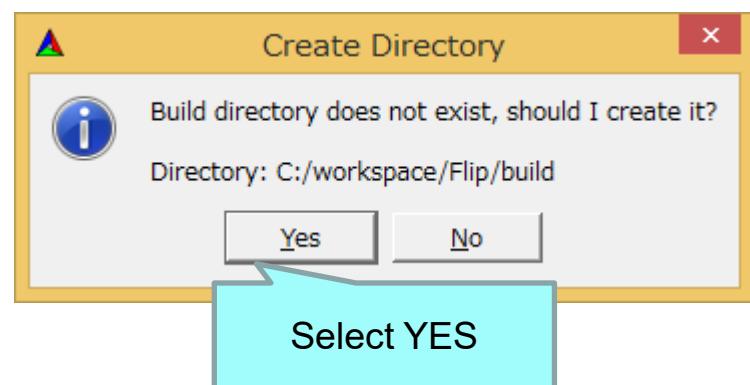
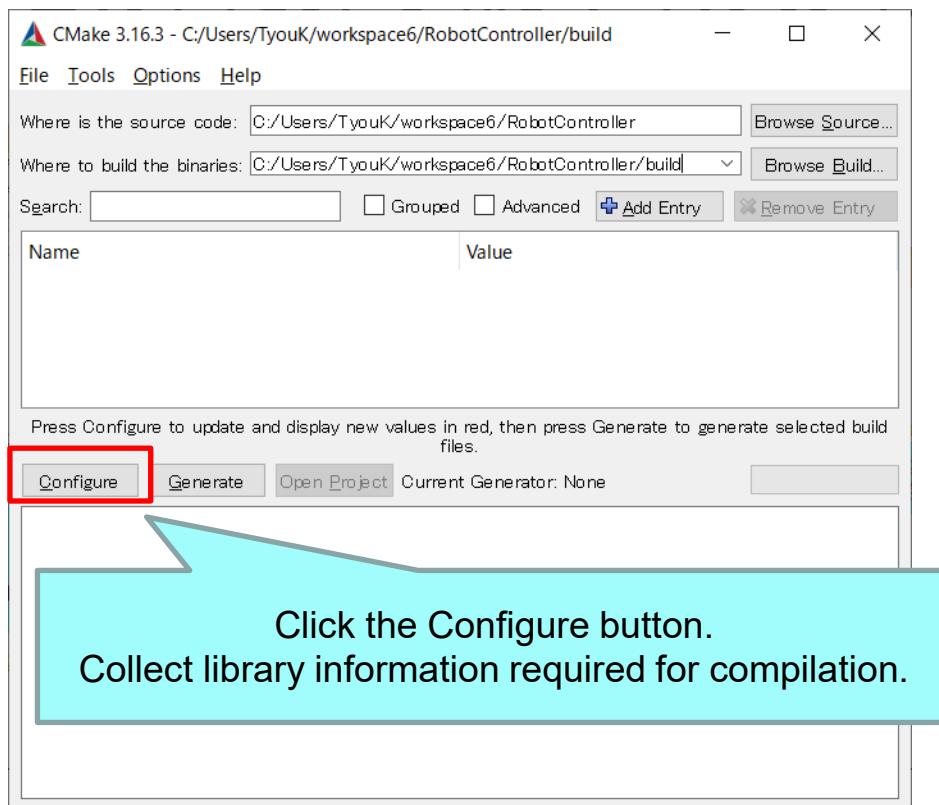
Configure

Generate

Open Project

Current Generator: None

ビルドに必要なファイルの生成



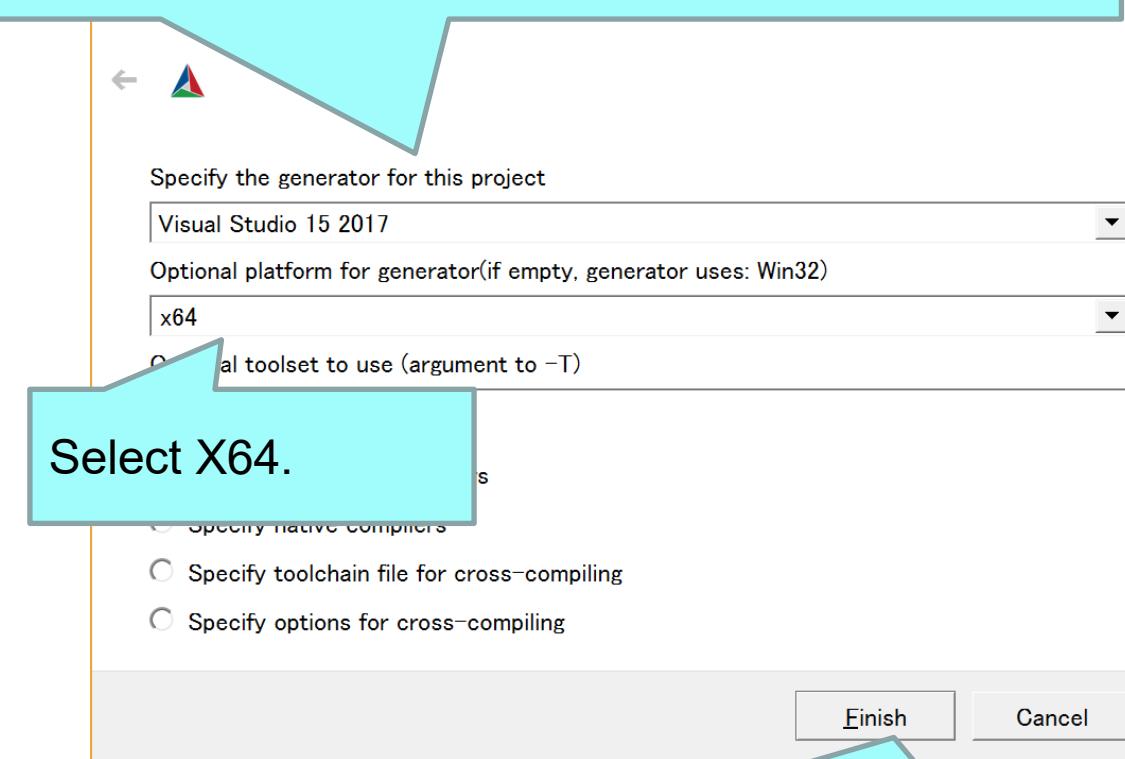
For CMake 3.14 or later

Build environment settings

Visual Studio 2017 → Visual Studio 15 2017

Visual Studio 2013 → Visual Studio 12 2013

Code::Blocks → CodeBlocks-Unix Makefiles



After setting, press the Finish button.

CMake 3.13以前の場合

ビルド環境の設定

Visual Studio 2013 32bit → Visual Studio 12 2013

Visual Studio 2013 64bit → Visual Studio 12 2013 Win64

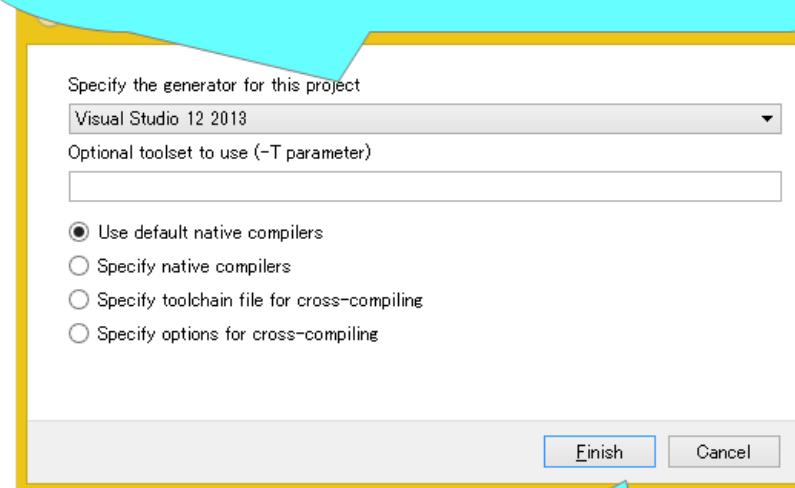
Visual Studio 2017 32bit → Visual Studio 15 2017

Visual Studio 2017 64bit → Visual Studio 15 2017 Win64

Code::Blocks → CodeBlocks-Unix Makefiles

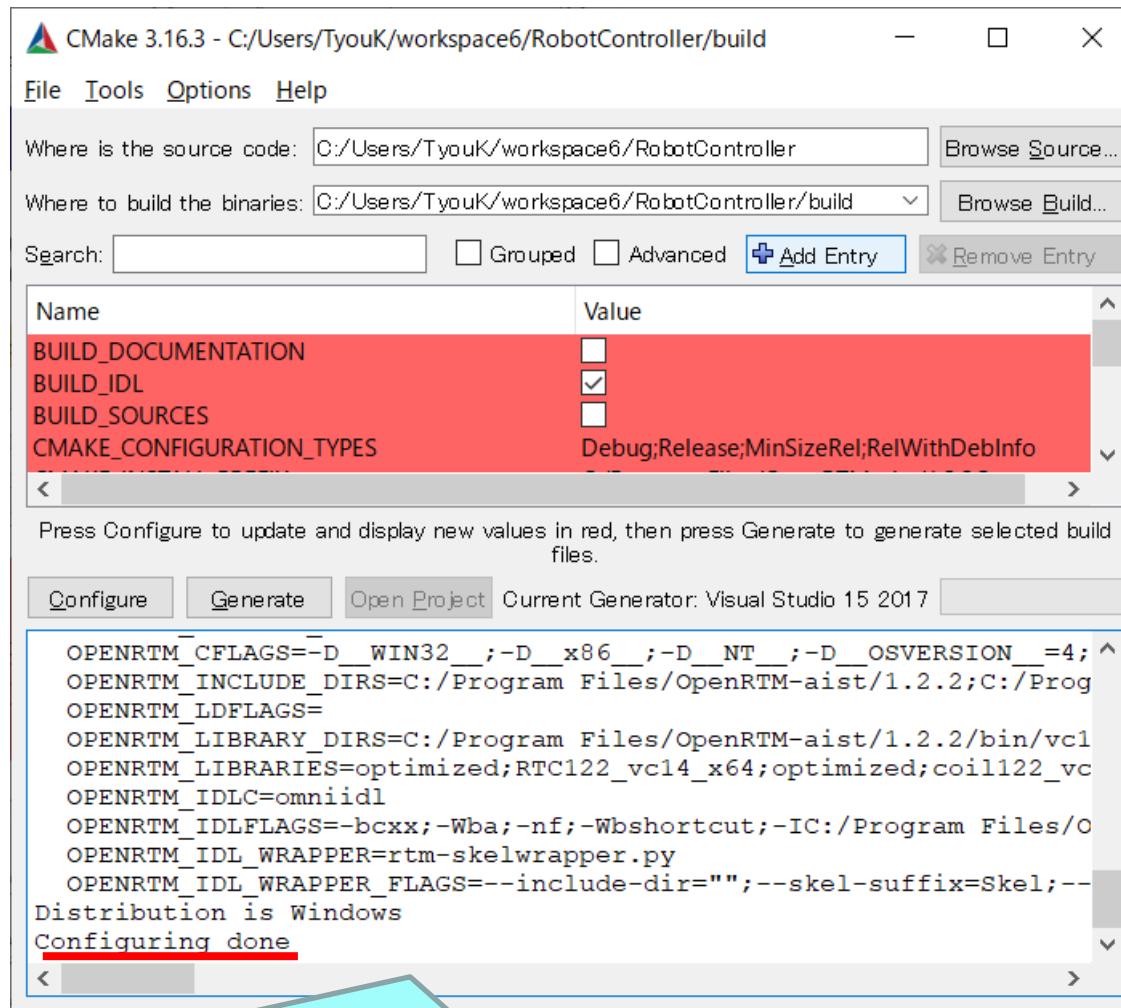
※32bitか64bitかはインストールした

OpenRTM-aistが32bitか64bitかで選択



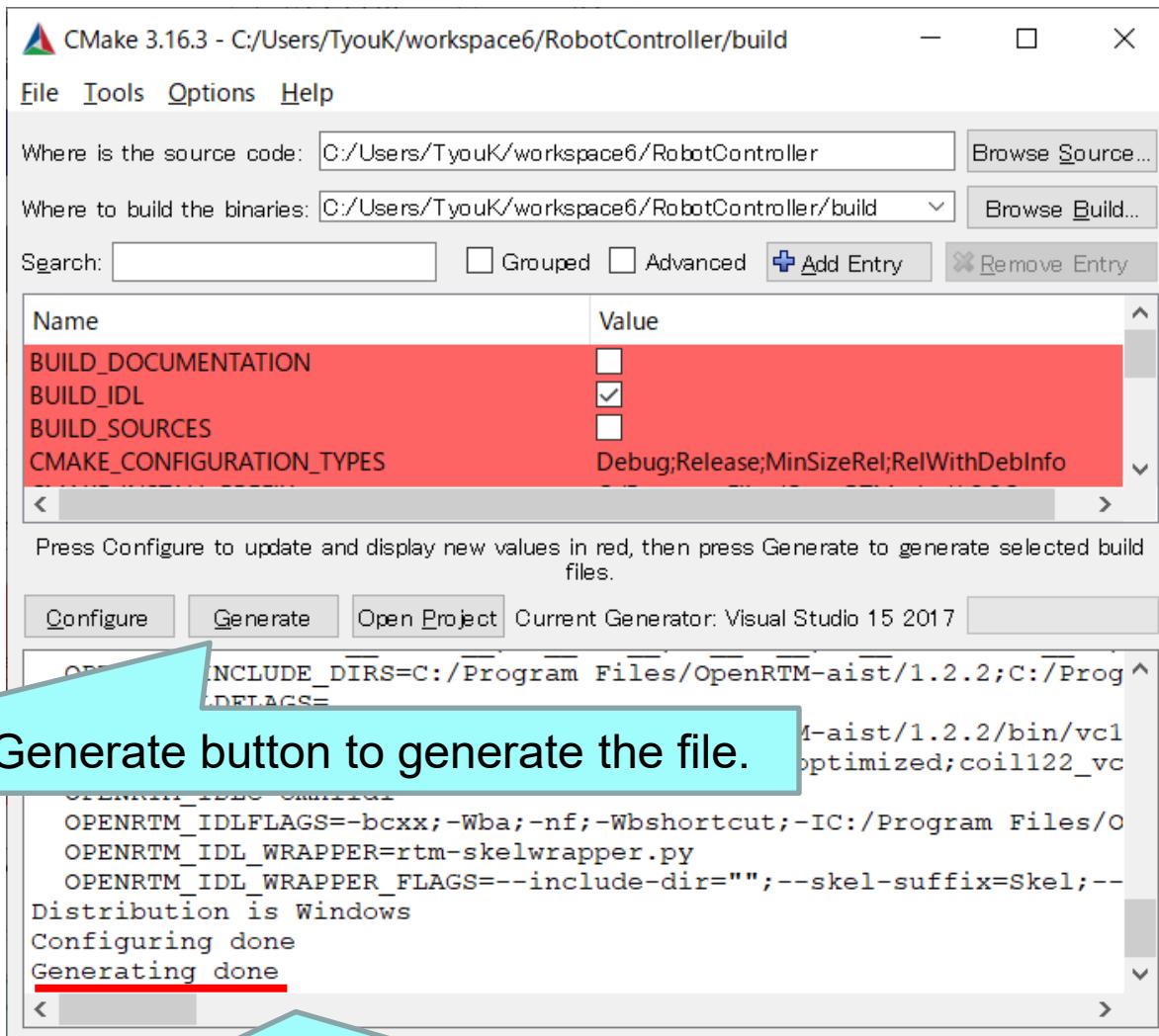
設定後、Finishボタンを押す

Generating files needed for build



If "Configure done" is displayed, it is successful.

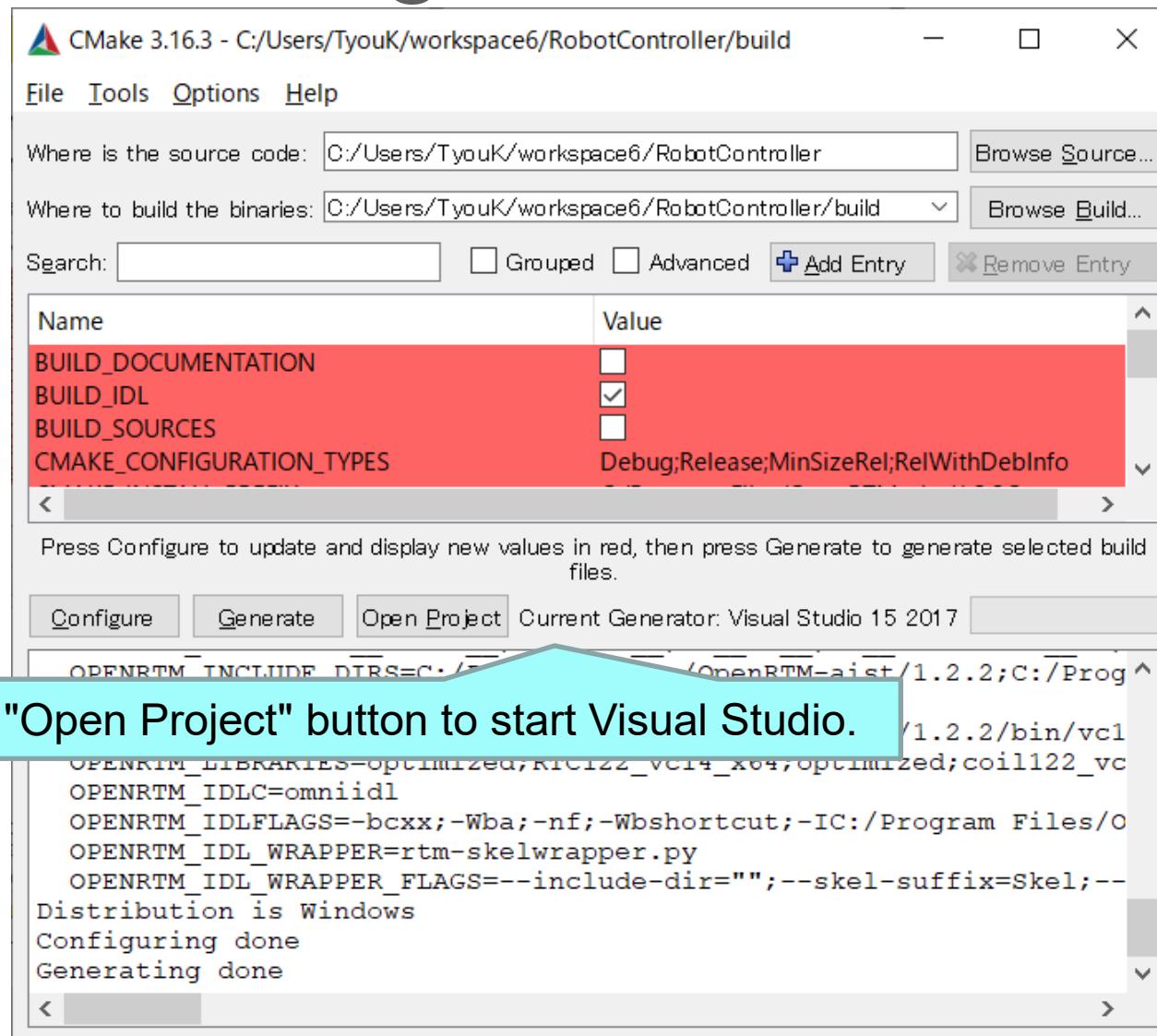
Generating files needed for build



Click the Generate button to generate the file.

If "Generating done" is displayed, it is successful.

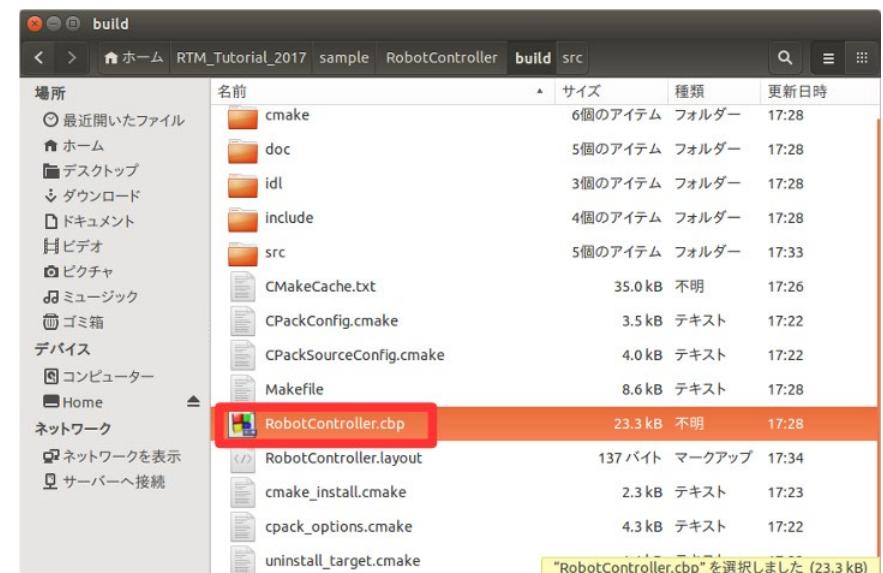
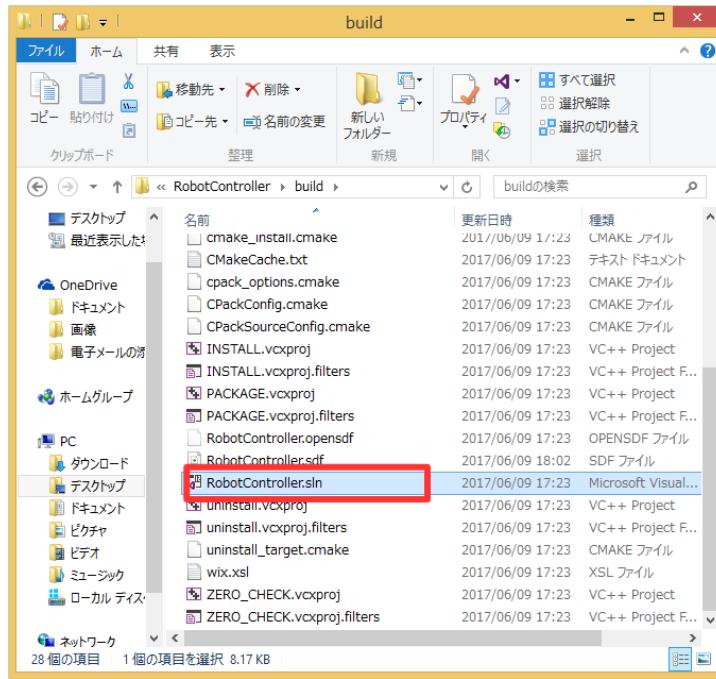
Editing source code



Click the "Open Project" button to start Visual Studio.

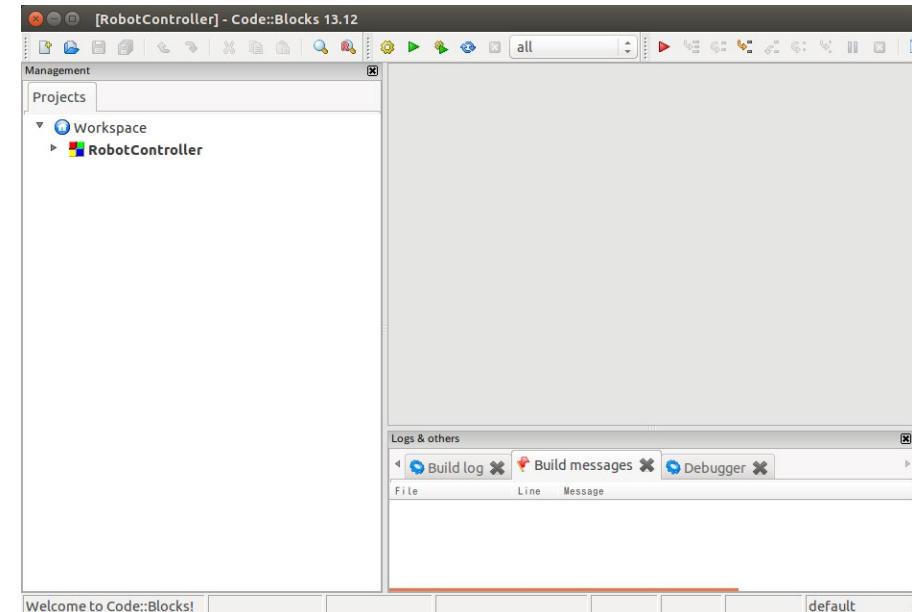
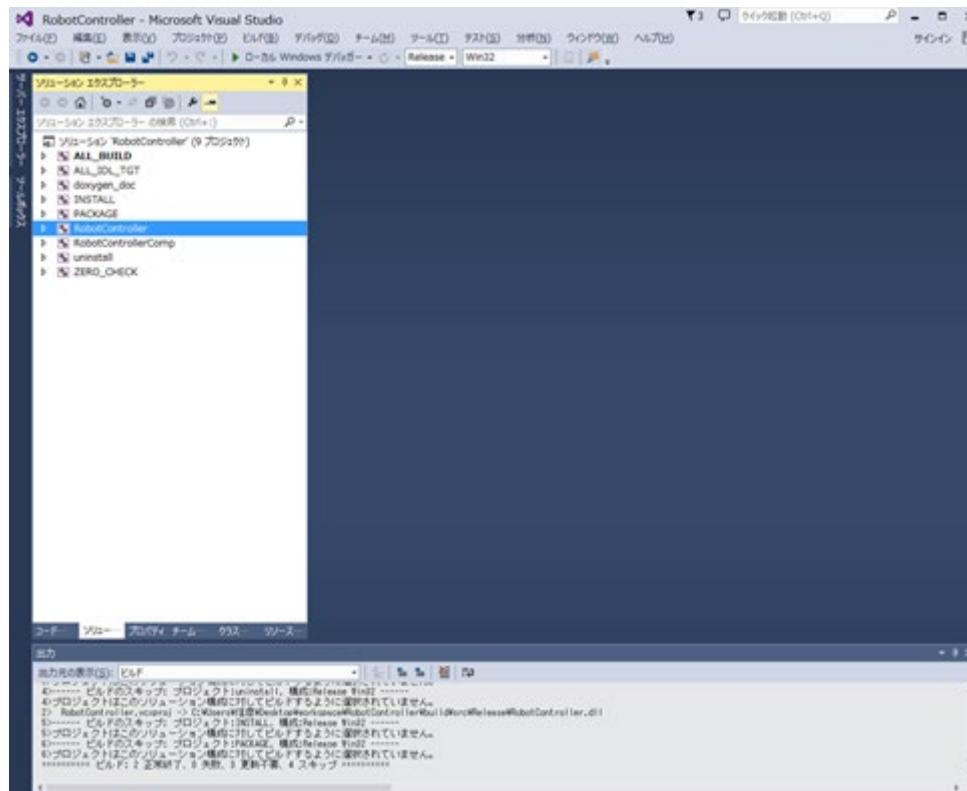
Editing source code

- If the version of CMake-gui is old, there is no "Open Project" button, so double-click the file to open it.
 - Windows
 - Left-click "RobotController.sln" in the build folder to open it
 - Ubuntu
 - Double-click "RobotController.cbp" in the build folder to open it.



Editing source code

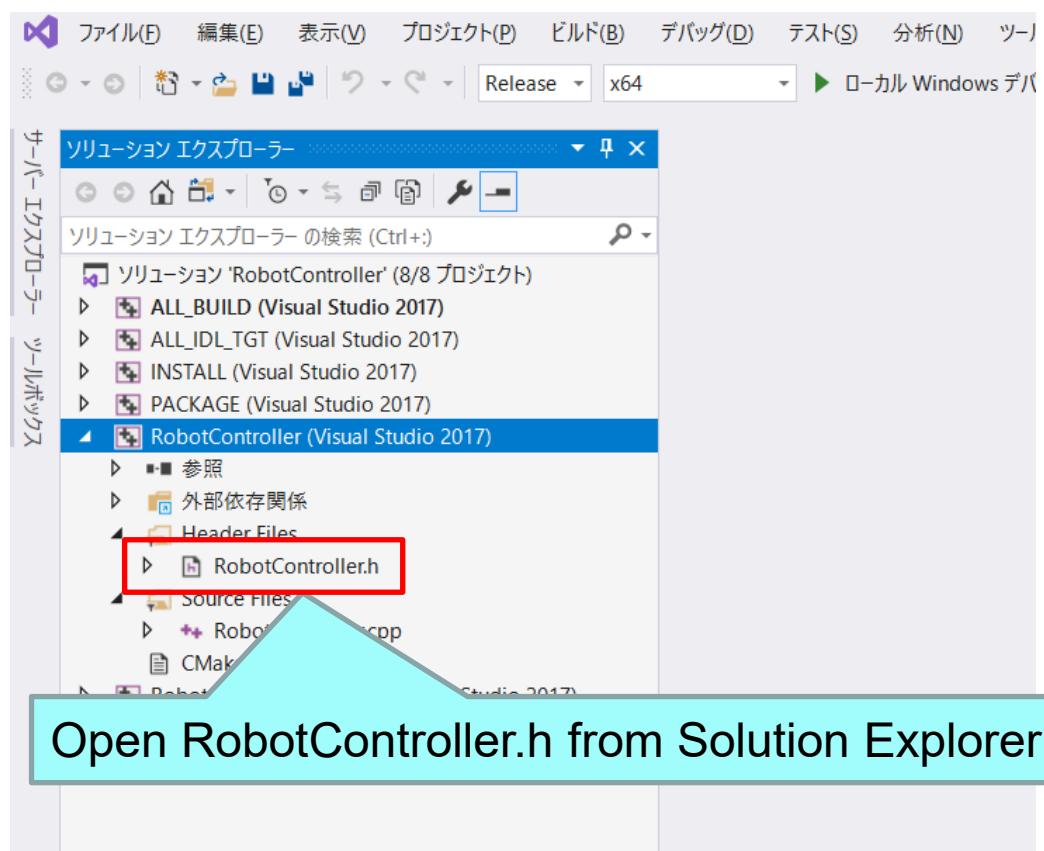
- Windows
 - Visual Studio starts
- Ubuntu
 - Code::Blocks starts



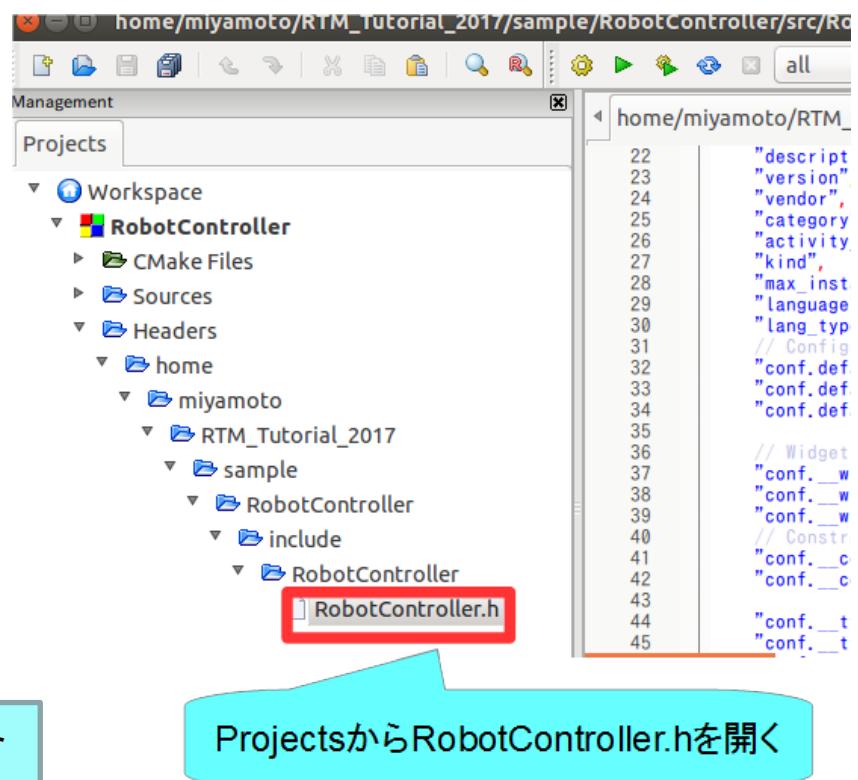
Editing source code

- Edit RobotController.h

Visual Studio



Code::Blocks



Editing source code

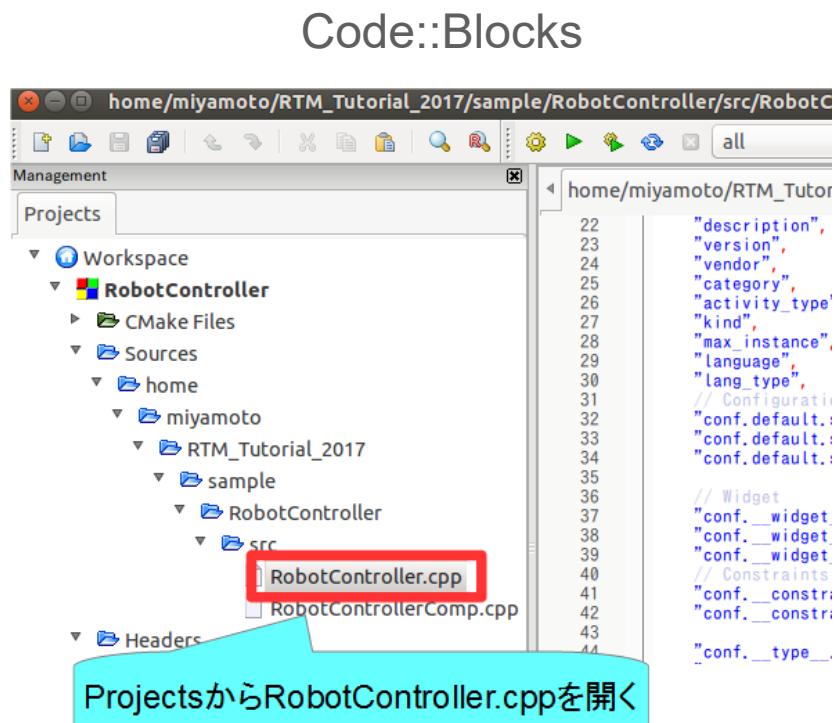
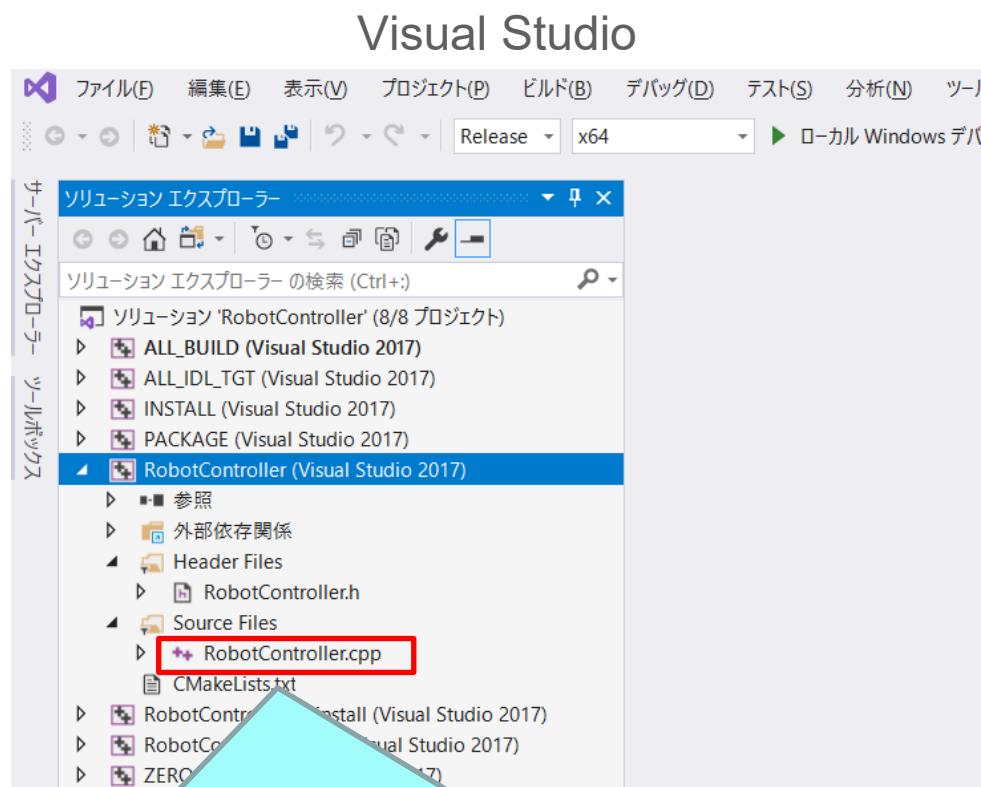
- Edit RobotController.h

```
265 Declaration of a variable that temporarily stores the sensor value
266
267 int sensor_data[4];
268
```

```
269 ↓
270 private: ↓
271     int sensor_data[4]; ↓
272     // <rtc-template block="private_attribute">↓
273     ↓
274     // </rtc-template>↓
275     ↓
276     // <rtc-template block="private_operation">↓
277     ↓
278     // </rtc-template>↓
279     ↓
280 }; ↓
281 ↓
282 ↓
283 extern "C" ↓
284 { ↓
```

Editing source code

- Edit RobotController.cpp



Open RobotController.cpp from Solution Explorer

Editing source code

- Edit RobotController.cpp

```
125 RTC::ReturnCode_t RobotController::onActivated(RTC::UniqueId ec_id) {  
126     //Sensor value initialization  
127     for (int i = 0; i < 4; i++) {  
128         sensor_data[i] = 0;  
129     }  
130     return RTC::RTC_OK;  
131 }  
132  
133 }  
134 }
```

Added to onActivated function

```
137 RTC::ReturnCode_t RobotController::onDeactivated(RTC::UniqueId ec_id) {  
138     //Stop the robot  
139     m_out.data.vx = 0;  
140     m_out.data.va = 0;  
141     m_outOut.write();  
142     return RTC::RTC_OK;  
143 }  
144 }  
145 }
```

Added to onDeactivated function

Editing source code

- Edit RobotController.cpp
 - If it is difficult to write, please copy and paste from the following page.
 - <https://openrtm.org/openrtm/ja/node/6550#toc20>

```
148 RTC::ReturnCode_t RobotController::onExecute(RTC::UniqueId ec_id) {  
149     //Confirmation of existence of input data  
150     if (m_inIn.isNew()) {  
151         //Input data read  
152         m_inIn.read();  
153         //At this point the input data is stored in m_in.  
154         for (int i = 0; i < m_in.data.length(); i++) {  
155             //Store input data in another variable  
156             if (i < 4) {  
157                 sensor_data[i] = m_in.data[i];  
158             }  
159         }  
160     }  
161     //Determine if you want to stop only when moving forward  
162     if (m_speed_x > 0) {  
163         for (int i = 0; i < 4; i++) {  
164             //Determine if the sensor value is greater than or equal to the set value  
165             if (sensor_data[i] > m_stop_d) {  
166                 //Stop if the sensor value is greater than or equal to the set value  
167                 m_out.data.vx = 0;  
168                 m_out.data.va = 0;  
169                 m_outOut.write();  
170                 return RTC::RTC_OK;  
171             }  
172         }  
173     }  
174     //If there is no sensor with a value higher than the set value, operate with the value of the configuration parameter.  
175     m_out.data.vx = m_speed_x;  
176     m_out.data.va = m_speed_r;  
177     m_outOut.write();  
178     return RTC::RTC_OK;  
179 }  
180 }  
181 }  
182 }  
183 }  
184 }  
185 }  
186 }  
187 }
```

Added to onExecute function

Editing source code

- Procedure to read data

```
148 RTC::ReturnCode_t Read()
149 {
150     //Confirmation of existence of input data
151     if (m_inIn.isNew())
152     {
153         //Input data read
154         m_inIn.read();
155         //At this point the input data is stored in m_in.
156         for (int i = 0; i < m_in.data.length(); i++)
157         {
158             ...
159             ...
160             ...
161             sensor_data[i] = m_in.data[i];
162         }
163     }
164 }
```

Check if there is newly written data with the isNew function

//Confirmation of existence of input data

if (m_inIn.isNew())

//Input data read

m_inIn.read();

//At this point the input data is stored in m_in.

for (int i = 0; i < m_in.data.length(); i++)

Data is stored in the variable m_in when the read function is called.

sensor_data[i] = m_in.data[i];

TimedShortSeq type holds multiple data like an array.

Editing source code

- Procedure for writing data

```
//Determine if you want to move straight
if (m_speed_x > 0) {
    for (int i = 0; i < sensor_data.length; i++) {
        //Determine if the sensor value is greater than or equal to the set value
        if (sensor_data[i] >= m_stop_d) {
            //Stop if the sensor value is greater than or equal to the set value
            m_out.data.vx = 0;
            m_out.data.va = 0;
            m_outOut.write();
            return RTC::RTC_OK;
        }
    }
    //If there is no sensor with a value
    m_out.data.vx = m_speed_x;
    m_out.data.va = m_speed_r;
    m_outOut.write();
    return RTC::RTC_OK;
}
```

Store data in the variable m_out.

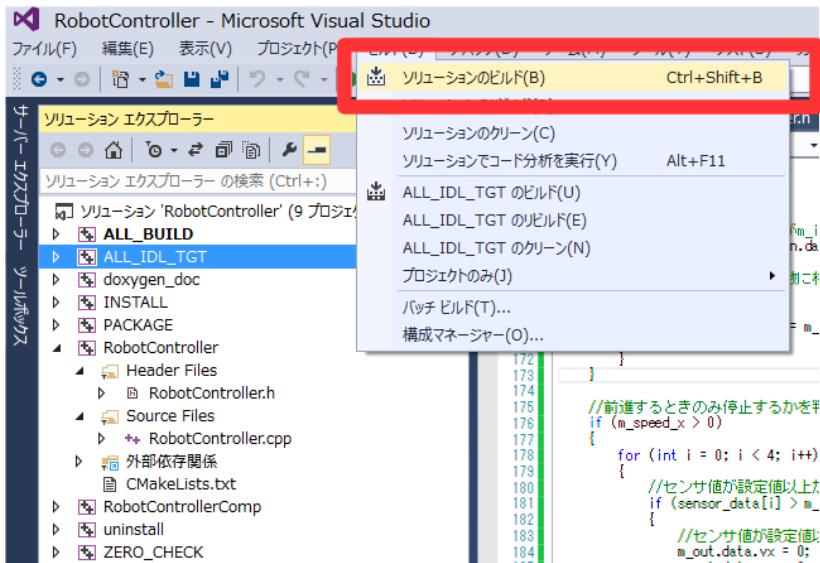
Since it is a TimedVelocity2D type, the straight speed is stored in vx and the rotation speed is stored in va.

When the configuration parameter is changed, the value is stored in the corresponding variable (m_speed_x, m_speed_r, m_stop_d).

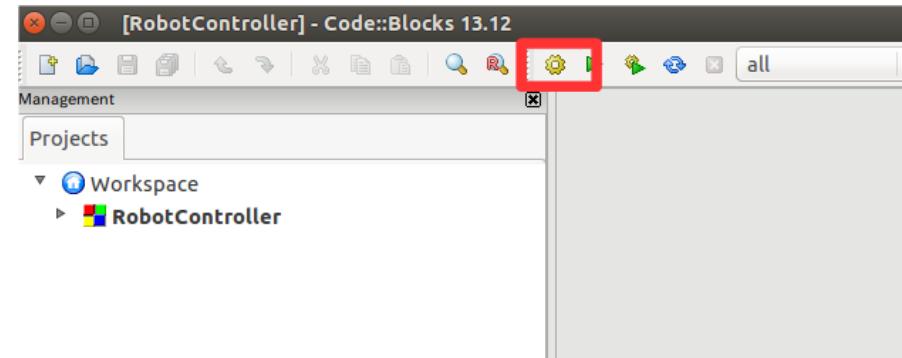
Write data with write function

RTC build

Visual Studio



Code::Blocks



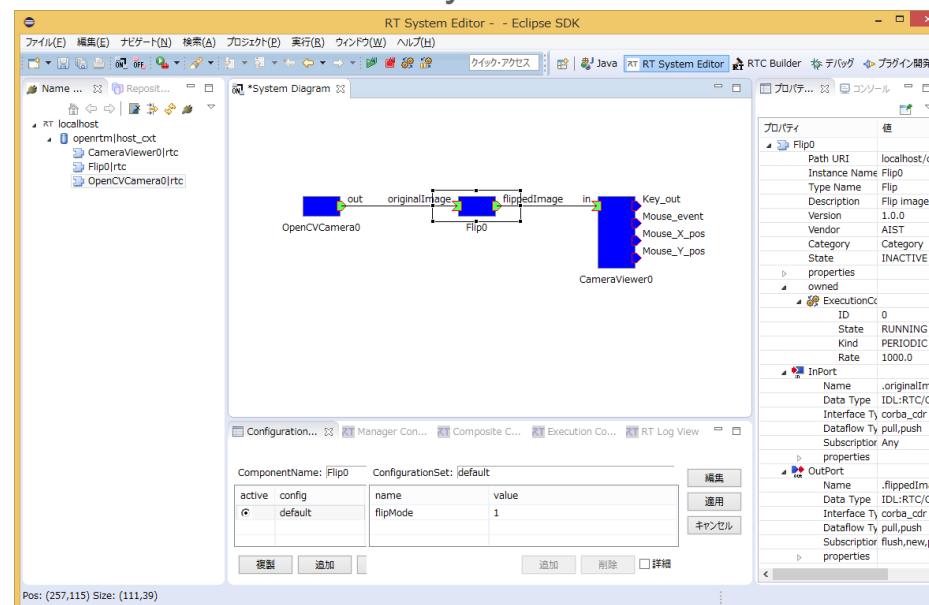
- If successful, an executable file will be generated.
 - Windows
 - RobotControllerComp.exe is generated in the Release (or Debug) folder of the build\src folder.
 - Ubuntu
 - RobotControllerComp is generated in the build/src folder

System construction support tool

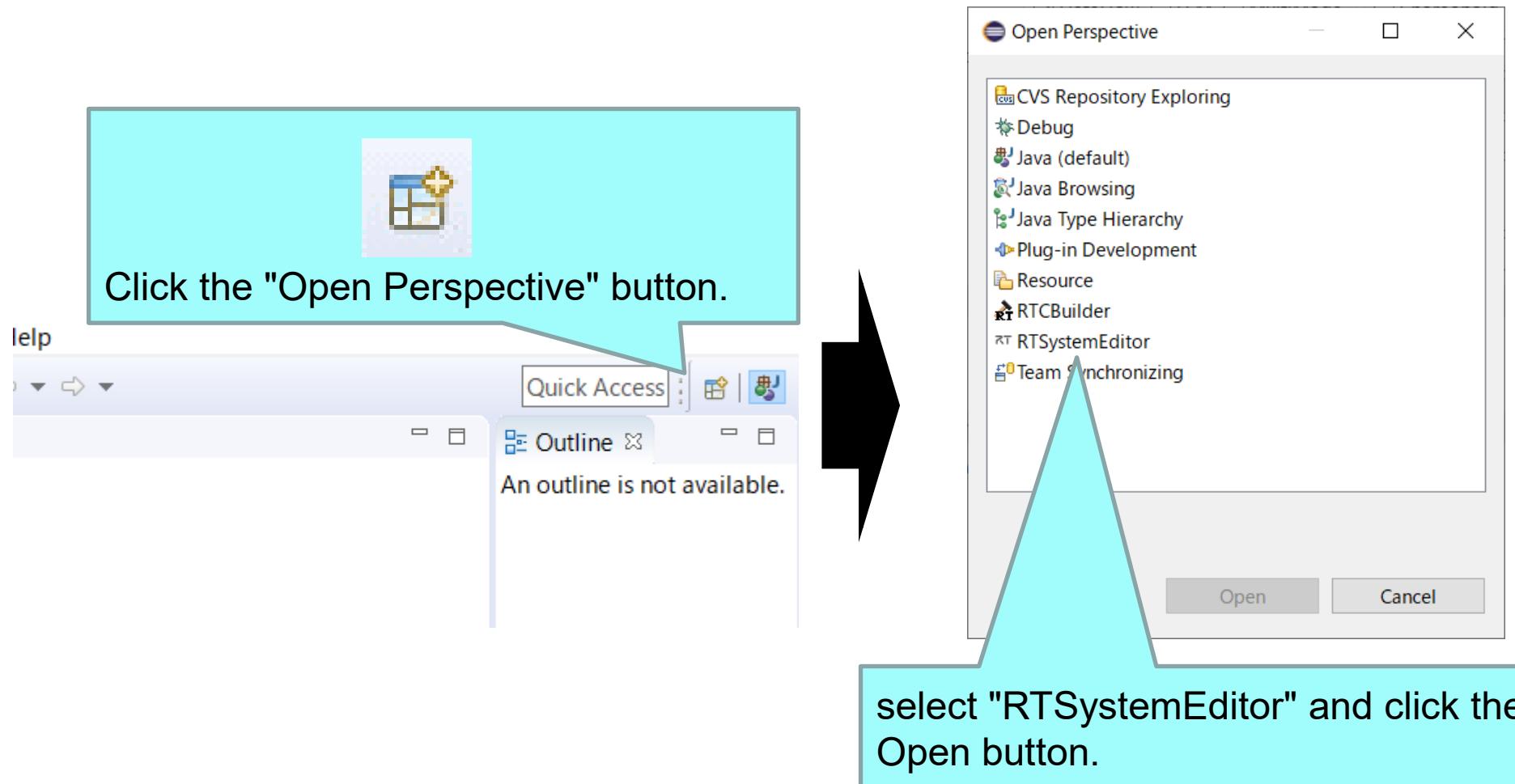
RT System Editor

RT System Editor

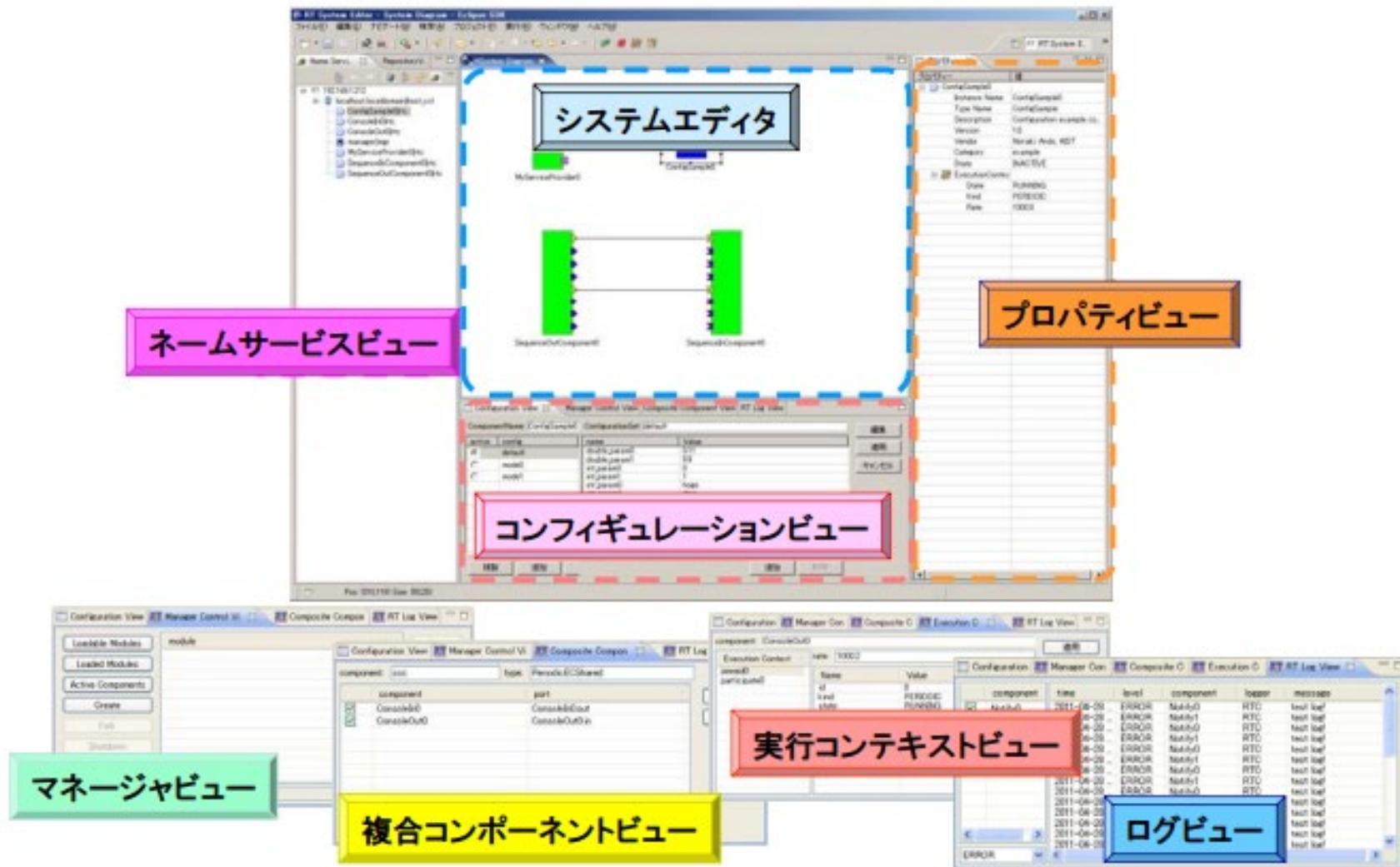
- Tool for operating RTC with GUI
 - Data port and service port connection
 - Activate, deactivate, reset, exit
 - Manipulating configuration parameters
 - Manipulating the execution context
 - Change execution cycle
 - Execution context association
 - Composite
 - Launch RTC from manager
 - Save and restore the created RT system



Start RTSYSTEMEDITOR

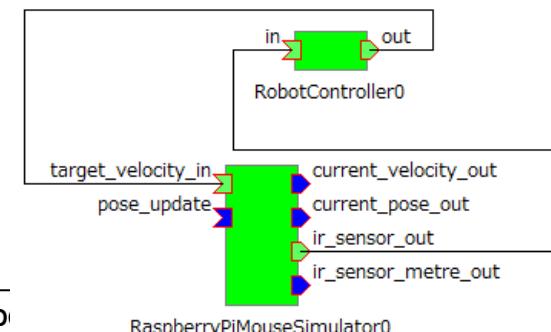


RT System Editor screen configuration



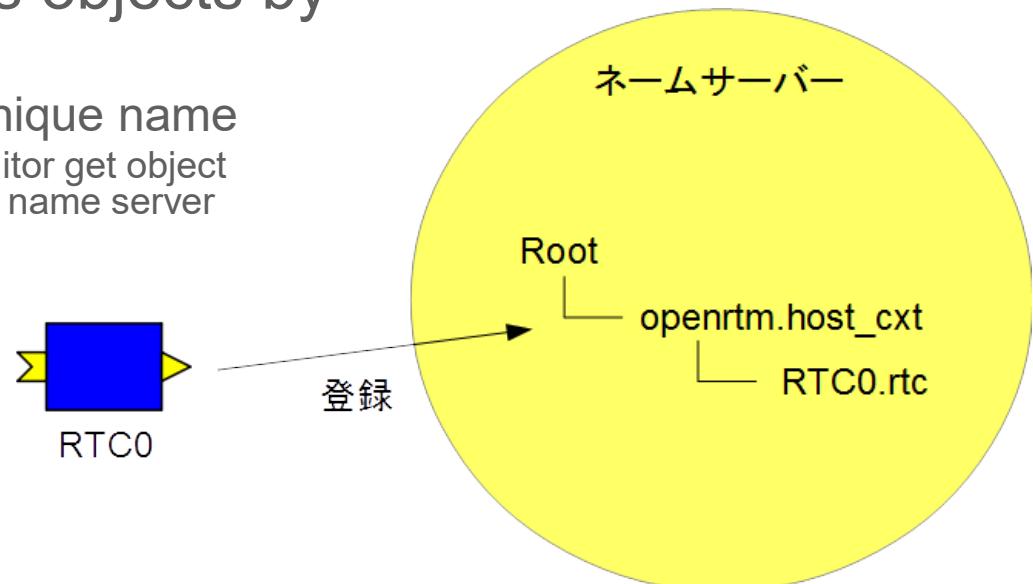
Operation check of RobotController component

- Create an RT system that connects to simulator components and operates robots on the simulator
 - Start Naming Service
 - Start RaspberryPiMouseSimulator Component
 - Windows
 - In the EXE folder of the extracted ZIP file
 - Double-click "RaspberryPiMouseSimulatorComp.exe"
 - Ubuntu
 - If not installed
 - » \$ wget https://raw.githubusercontent.com/OpenRTM/RTM_Tutorial_ROBOME_CH2019/master/script/install_raspimouse_simulator.sh
 - » \$ sh install_raspimouse_simulator.sh
 - Go to the RasPiMouseSimulatorRTC directory and enter the following command
 - » \$ build/src/RaspberryPiMouseSimulatorComp
 - Start RobotController Component
 - Connect the RaspberryPiMouseSimulator component and RobotController component and execute "All Activate"

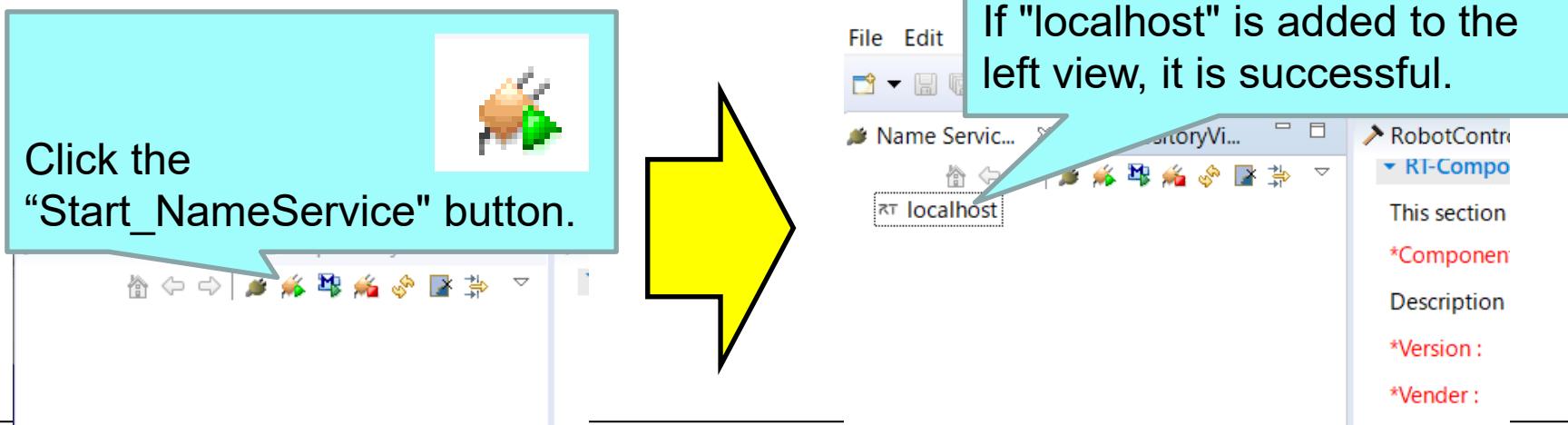


Naming Service

- A service that manages objects by name
 - Register the RTC with a unique name
 - Tools such as RT System Editor get object references by name from the name server



- Procedure to start



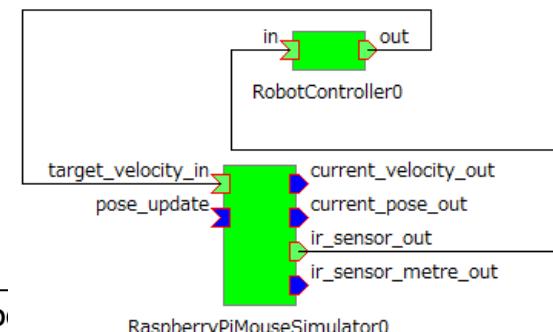
Start Naming Service

- OpenRTM-aist 1.1.2以前の手順
 - Windows 7
 - 「スタート」→「すべてのプログラム」→「OpenRTM-aist 1.2.0」→「Tools」→「Start Naming Service」
 - Windows 8.1
 - 「スタート」→「アプリビュー(右下矢印)」→「OpenRTM-aist 1.2.0」→「Start Naming Service」
 - Windows 10
 - 左下の「ここに入力して検索」にStart Naming Serviceと入力して起動
 - Ubuntu
 - \$ rtm-naming



Operation check of RobotController component

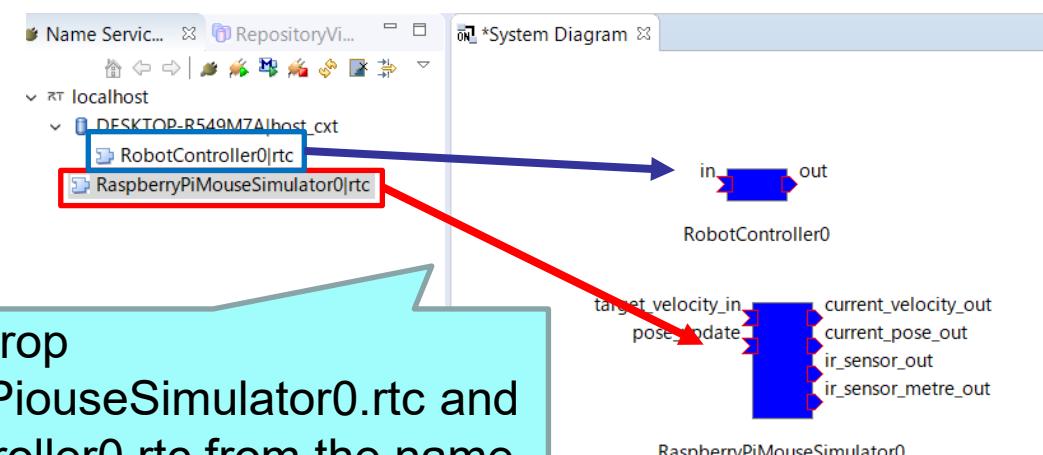
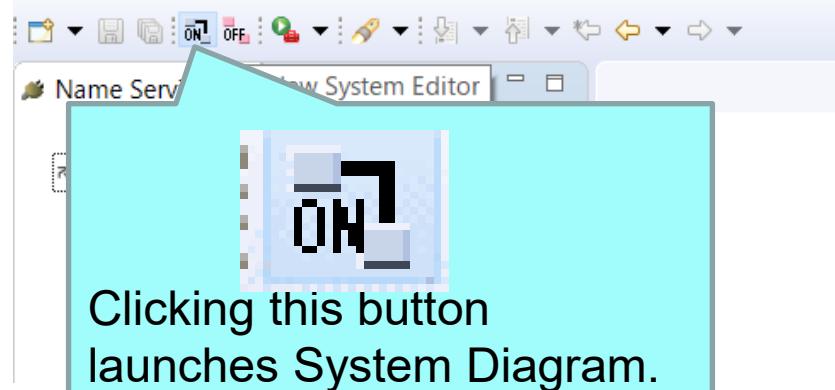
- Create an RT system that connects to simulator components and operates robots on the simulator
 - Start Naming Service
 - Start RaspberryPiMouseSimulator Component
 - Windows
 - In the EXE folder of the extracted ZIP file
 - Double-click "RaspberryPiMouseSimulatorComp.exe"
 - Ubuntu
 - If not installed
 - » \$ wget https://raw.githubusercontent.com/OpenRTM/RTM_Tutorial_ROBOME_CH2019/master/script/install_raspimouse_simulator.sh
 - » \$ sh install_raspimouse_simulator.sh
 - Go to the RasPiMouseSimulatorRTC directory and enter the following command
 - » \$ build/src/RaspberryPiMouseSimulatorComp
 - Start RobotController Component
 - Connect the RaspberryPiMouseSimulator component and RobotController component and execute "All Activate"



Data port connection

workspace6 - Eclipse SDK

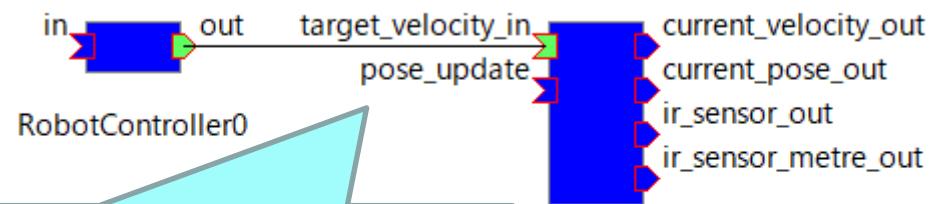
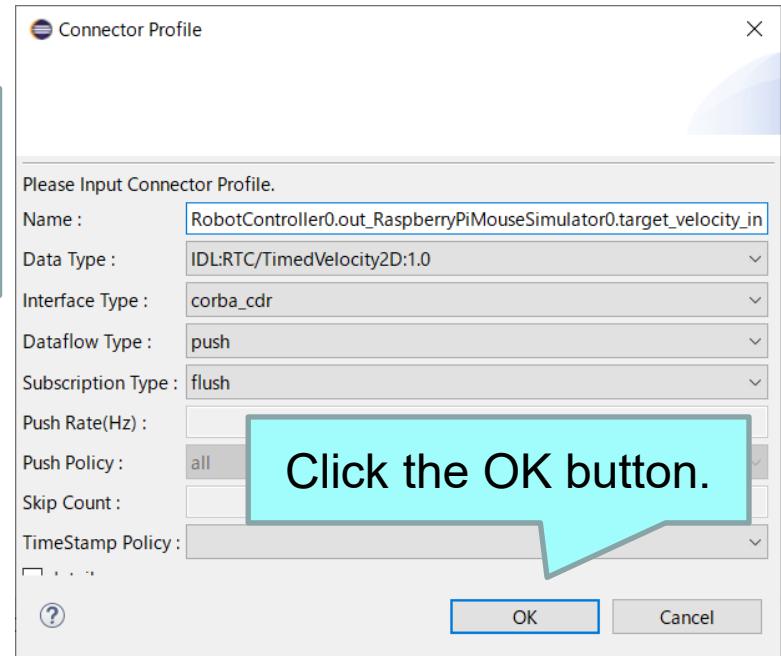
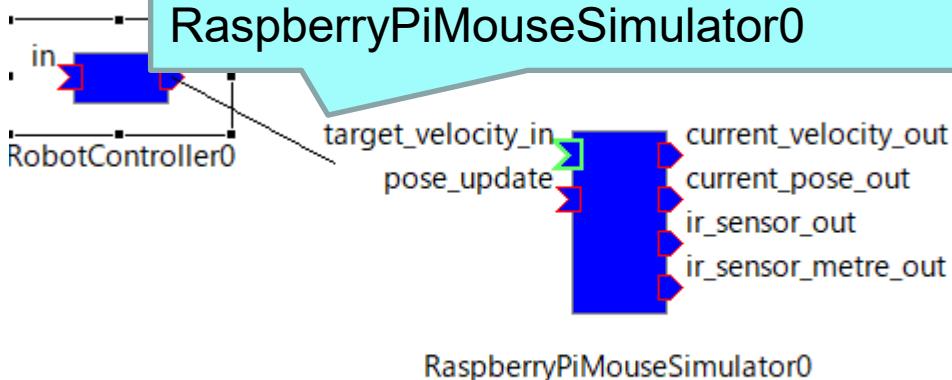
File Edit Navigate Search Project Run Window Help



Drag and drop
RaspberryPiouseSimulator0.rtc and
RobotController0.rtc from the name
service view on the left to the
System Diagram.

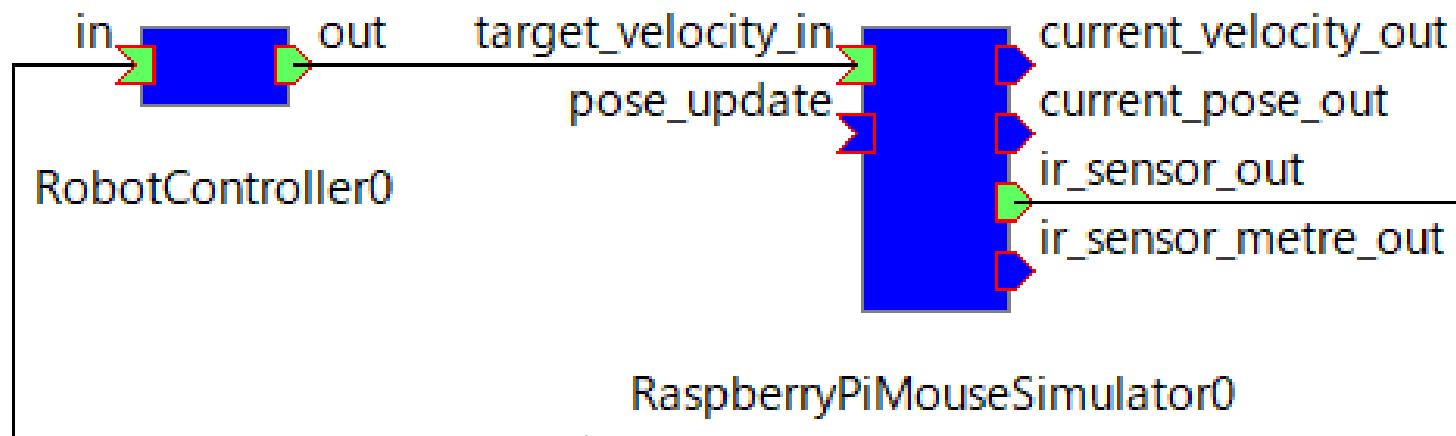
Data port connection

Drag and drop "out" of RobotController0 to "target_velocity_in" of RaspberryPiMouseSimulator0



1. A line appears between the ports
2. InPort and OutPort are displayed in green

Data port connectionの接続

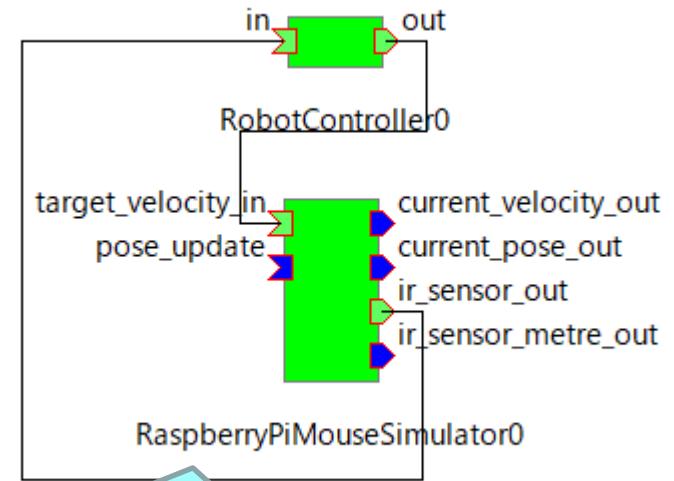
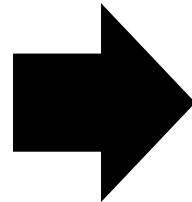
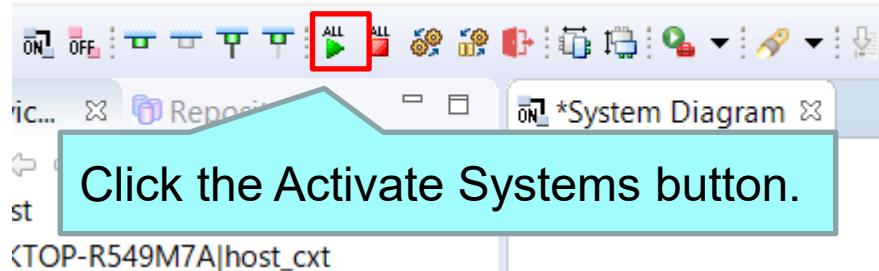


Connect "ir_sensor_out" of RaspberryPiSimulator0 and "in" of RobotController0.

Activation

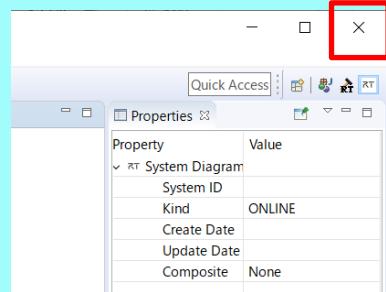
e6 - - Eclipse SDK

Navigate Search Project Run Window Help

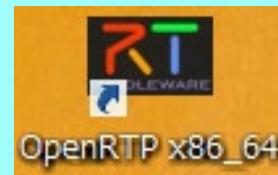


If the RTC changes green, activation is successful.

If the button does not appear, restart OpenRTP.



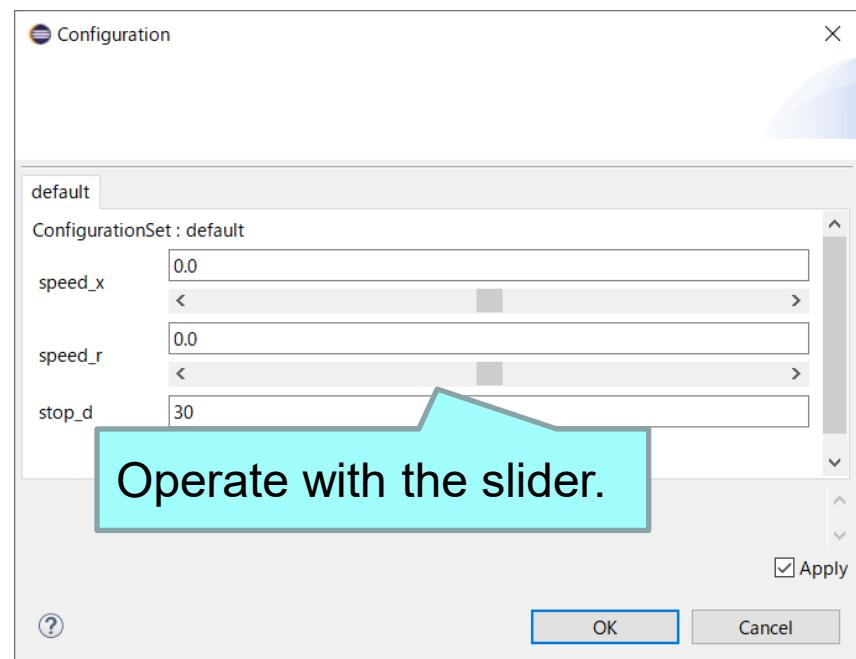
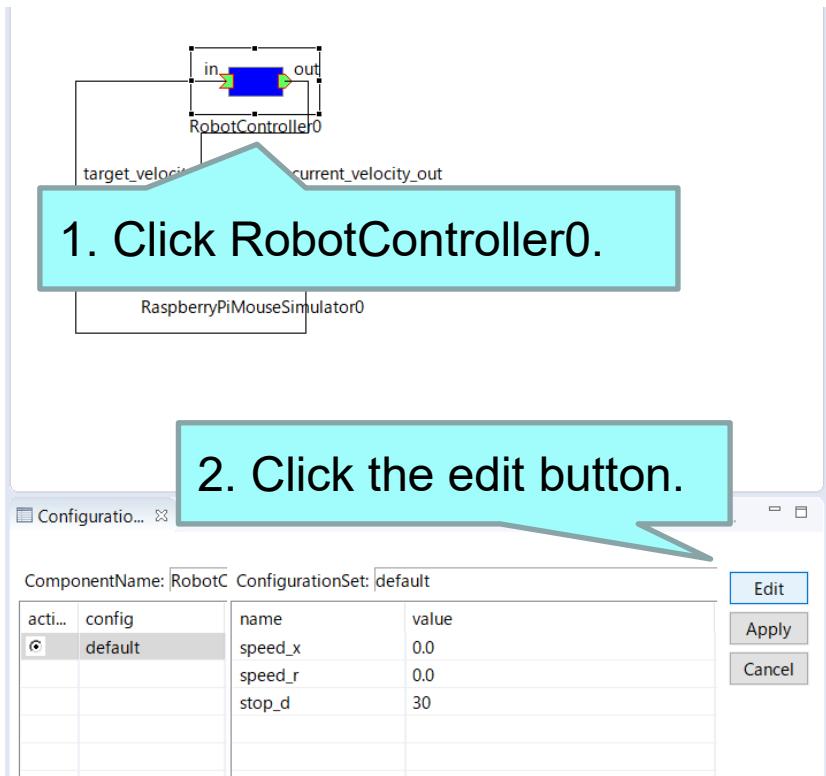
Exit OpenRTP.



Double-click on the shortcut.

Change configuration parameters

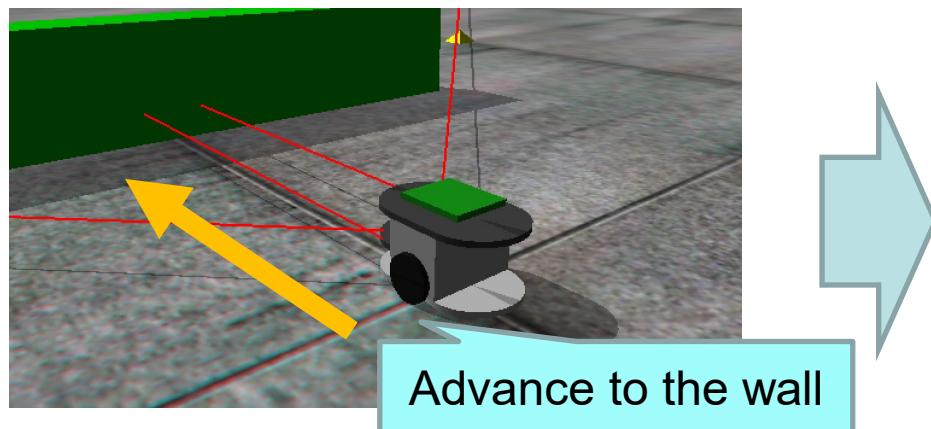
- Change configuration parameters using RT System Editor



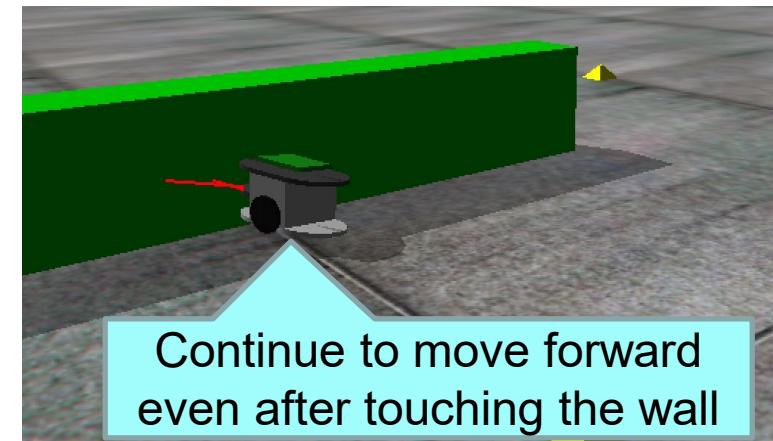
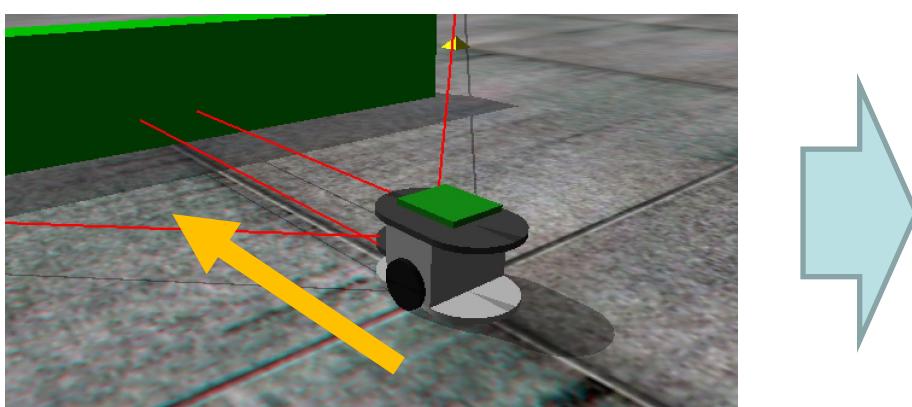
- Check if the following operations can be performed
 - Can the robot on the simulator be operated with the slider?
 - Does the robot stop when it approaches an wall?

動作確認

- When it stops when the wall approaches the distance sensor



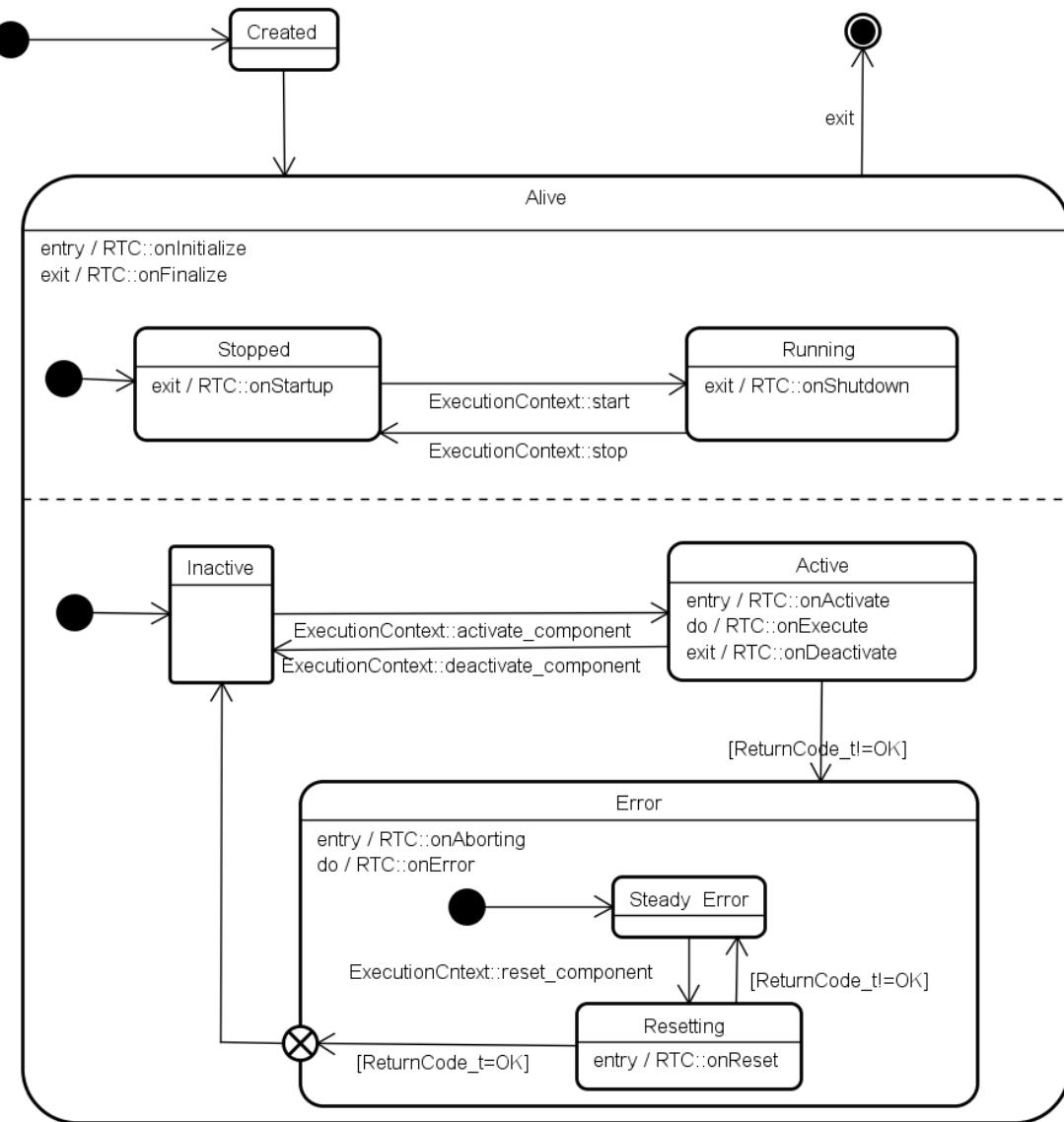
- When the wall does not stop when approaching the distance sensor



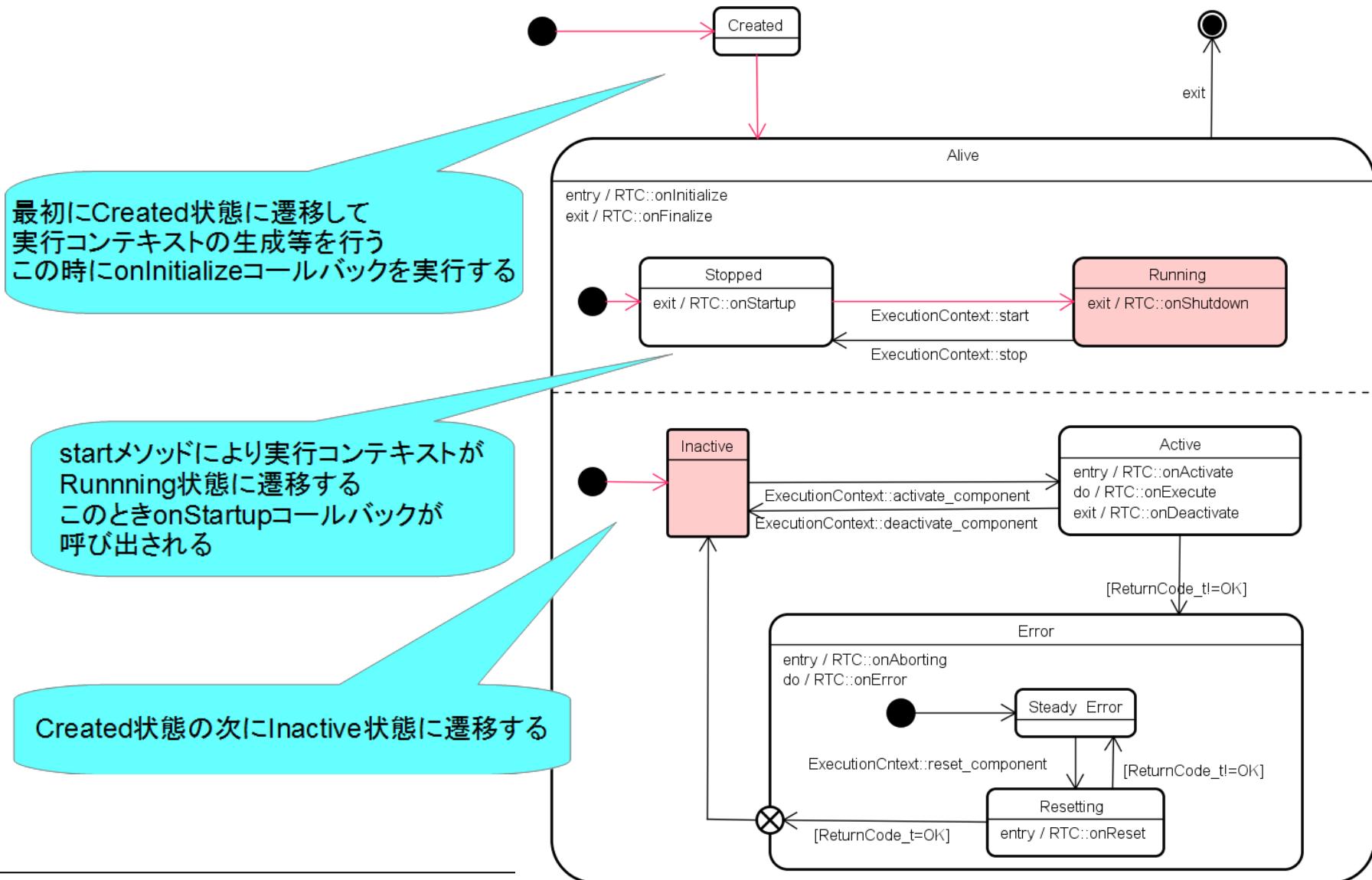
RTコンポーネントの状態遷移

- RTCには以下の状態が存在する

- Created
 - ・生成状態
 - ・実行コンテキストを生成し、start()が呼ばれて実行コンテキストのスレッドが実行中(Running)状態になる
 - ・自動的にInactive状態に遷移する
- Inactive
 - ・非活性状態
 - ・activate_componentメソッドを呼び出すと活性状態に遷移する
 - ・RT System Editor上での表示は青
- Active
 - ・活性状態
 - ・onExecuteコールバックが実行コンテキストにより実行される
 - ・リターンコードがRTC_OK以外の場合はエラー状態に遷移する
 - ・RT System Editor上での表示は緑
- Error
 - ・エラー状態
 - ・onErrorコールバックが実行コンテキストにより実行される
 - ・reset_componentメソッドを呼び出すと非活性状態に遷移する
 - ・RT System Editor上での表示は赤
- 終了状態



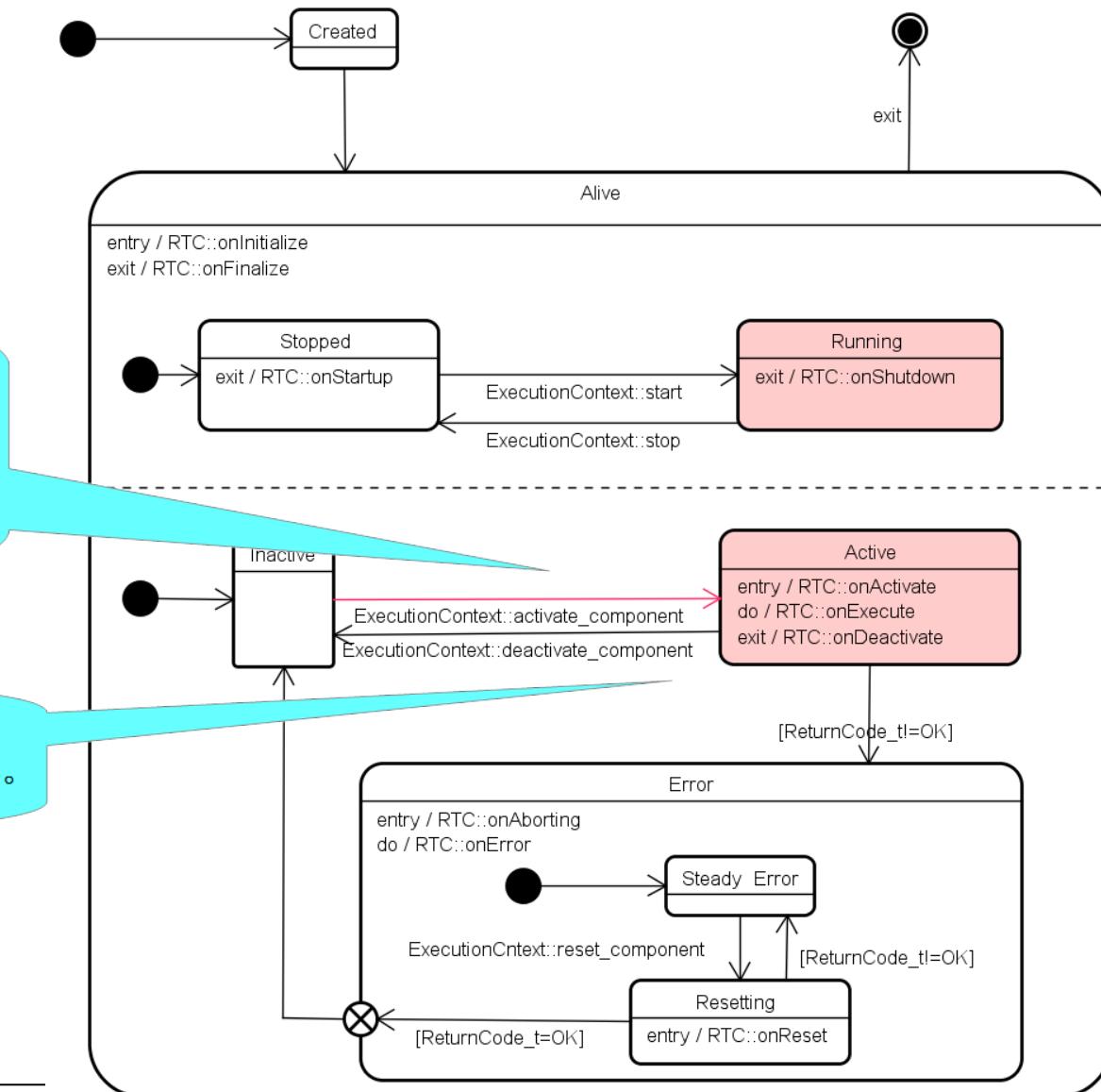
RTコンポーネントの状態遷移(生成直後)



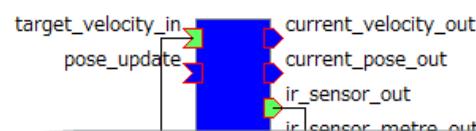
RTコンポーネントの状態遷移(アクティブ化)

RTシステムエディタの操作によりRTコンポーネントのアクティブ化を行うとactivate_componentメソッドが呼び出される。
 activate_componentメソッドによりコンポーネントがActive状態に遷移する。
 この時onActivatedコールバックが実行される

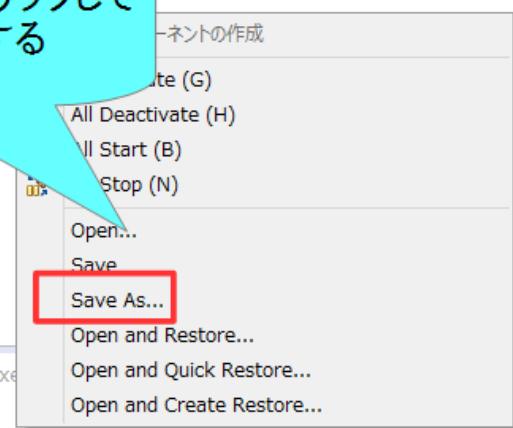
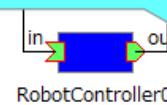
周期実行の実行コンテキストの場合、
 onExecuteコールバックが周期的に呼び出される。



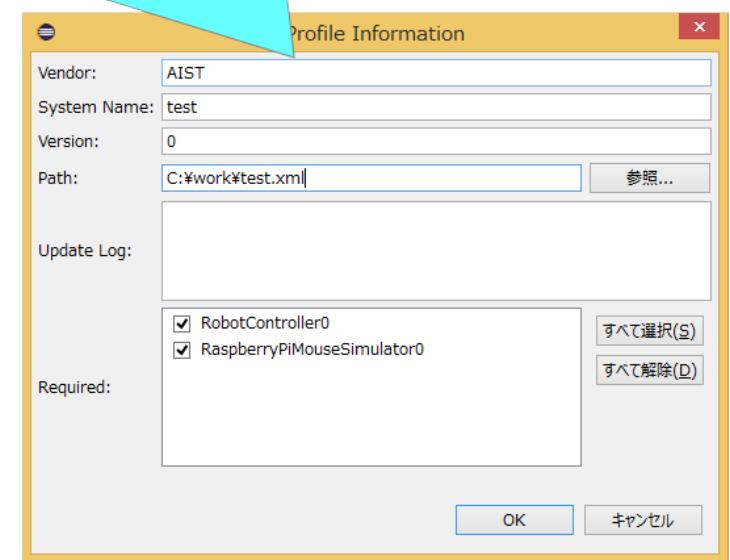
システムの保存



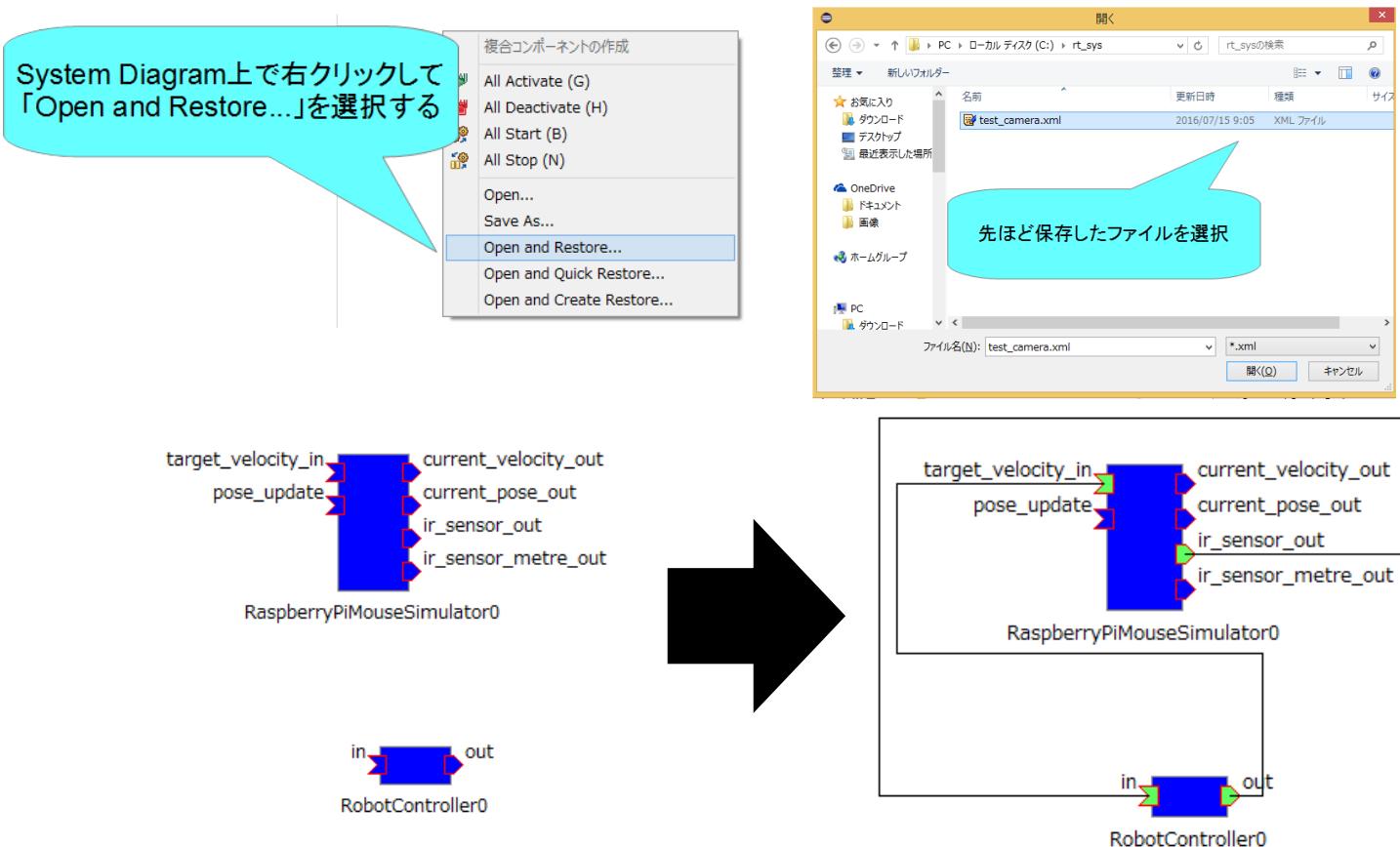
System Diagram上で右クリックして
「Save As...」を選択する



ベンダ名、システム名、バージョン、保存ファイル名を入力



システムの復元



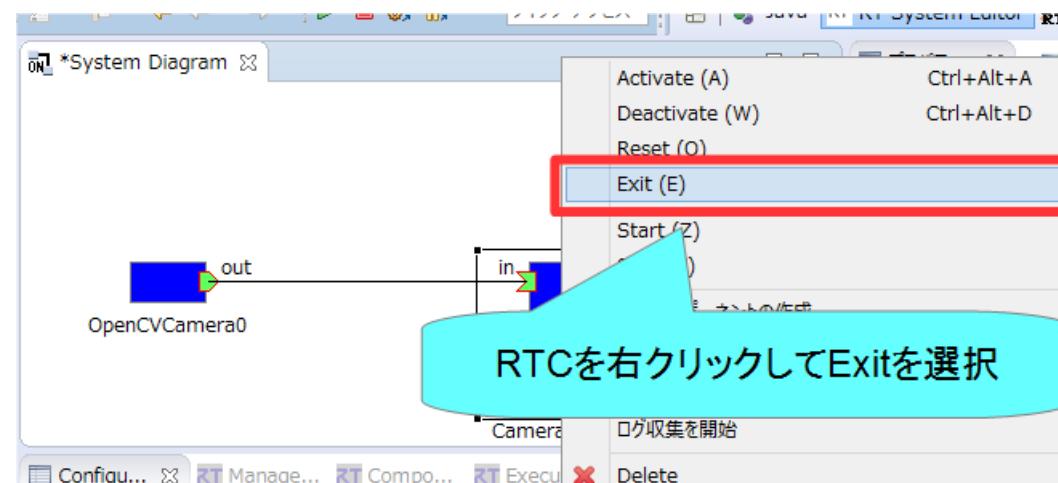
- 以下の内容を復元
 - ポート間の接続
 - コンフィギュレーション
 - 「Open and Create Restore」を選択した場合はマネージャからコンポーネント起動

非アクティブ化、終了

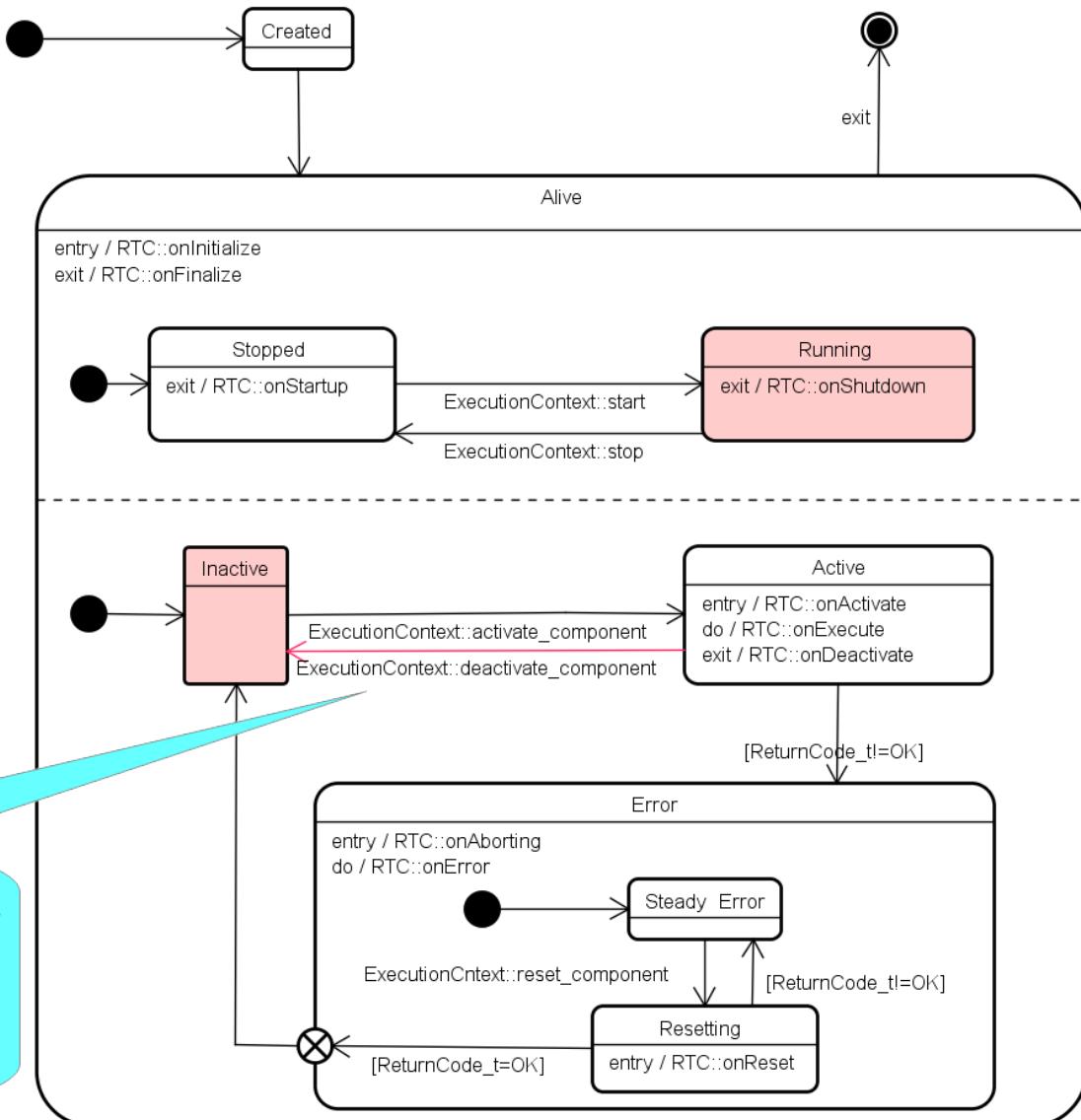
- 非アクティブ化



- 終了



RTコンポーネントの状態遷移(非アクティブ化)



Raspberry Piマウス実機との接続

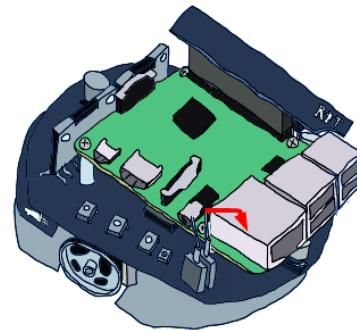
- Raspberry PiとノートPCを無線LANで接続
 - Raspberry Piが無線LANアクセスポイントになる



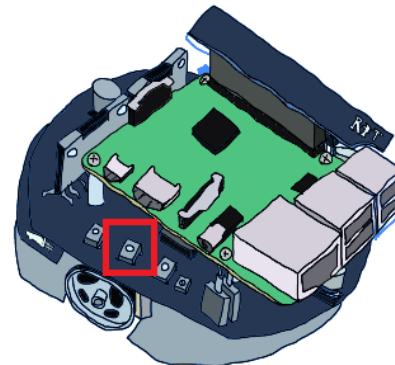
- 注意事項
 - ノートPCに複数のネットワークインターフェースが存在する場合にRTCの通信ができない可能性があります。
 - 問題が発生した場合は個別に対応します。
 - Raspberry Piアクセスポイント接続後はインターネットに接続できなくなります。
 - Raspberry Piアクセスポイント接続後に、**起動済みのネームサーバーとRTCは再起動してください。**
 - Raspberry Piはシャットダウンしてから電源スイッチをオフにするようにしてください
 - モーター電源スイッチはこまめに切るようにしてください

Raspberry Piとの接続

- Raspberry Piの電源投入
 - 内側のスイッチをオンにする



- 電源を切る場合
 - 3つ並んだスイッチの中央のボタンを1秒以上押す
 - 10秒ほどでシャットダウンするため、その後に電源スイッチをオフにする



Raspberry Piとの接続

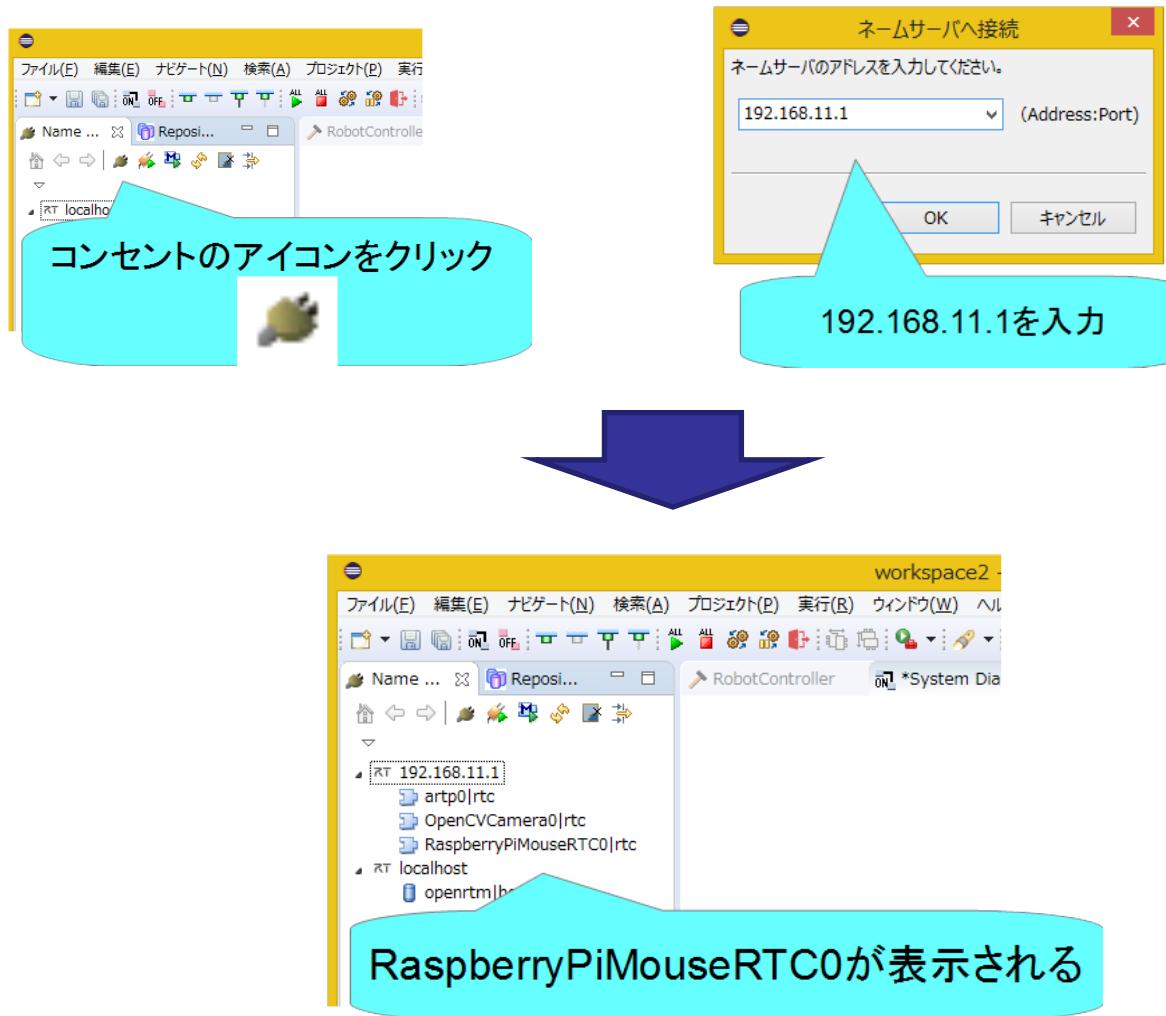
- 無線LANアクセスポイントとの接続
 - SSID、パスワードはRaspberry Piマウス上のシールに記載
 - 接続手順(Windows)
 - 画面右下のネットワークアイコンをクリック



- raspberrypi_xxに接続後、パスワードを入力

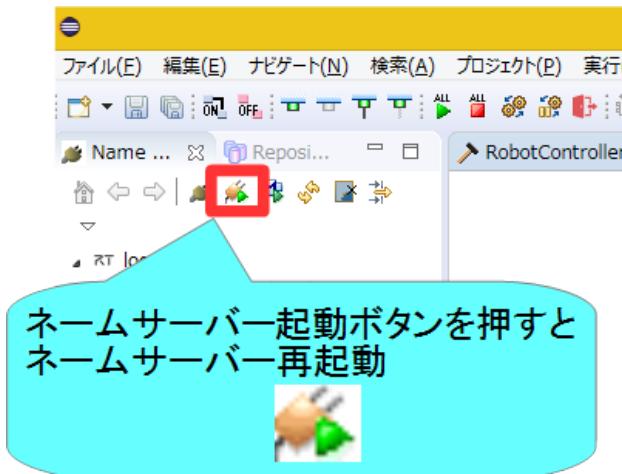


ネームサーバーとの接続



起動済みのRTC、ネームサーバー再起動

- ネームサーバーを再起動する
 - OpenRTM-aist 1.2の場合はネームサーバー起動ボタンで再起動

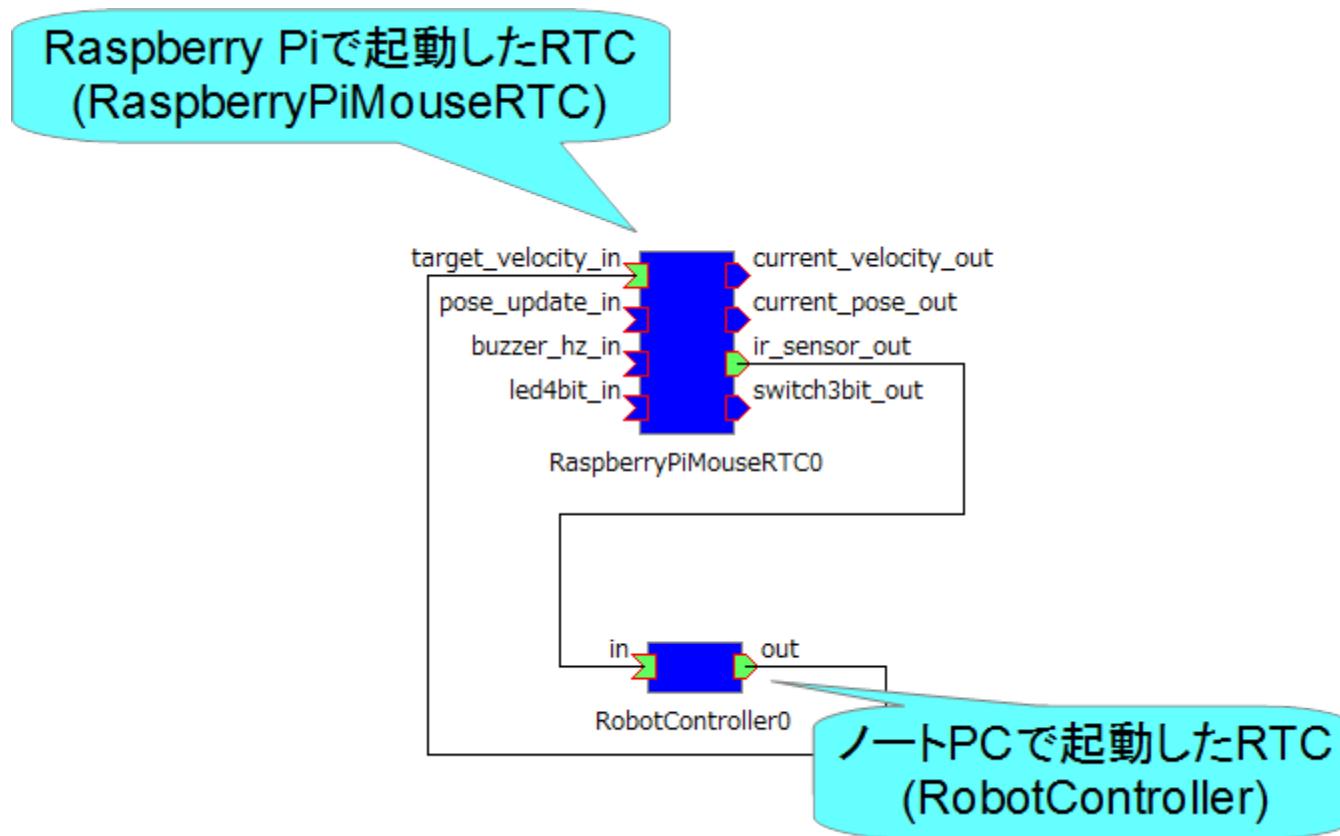


- OpenRTM-aist 1.1.2の場合はネームサーバーのプロセス終了後、「Start Naming Service」を再度実行
- RTC再起動
 - RTCをexitするか、RTC起動時に表示したウィンドウの×ボタンを押して終了する
 - 実行ファイル(RobotControllerComp.exe)を再度実行

```
C:\Users\信彦\Desktop\workspace\SpeechSample\build\src\Release... -> X
omniORB: (0) 2018-06-02 11:24:18.793000: Warning: the local loop back interface
(I27.0.0.1) is the only address available for this server.
- sync_transition: YES
- transition_timeout: 0.5
- type: PeriodicExecutionContext
- rate: 1000
- name:
- port:
  - port_type: DataOutPort
- dataport:
  - data_type: IDL:RTC/TimedString:1,0
  - source_type: types::new,new,periodic
  - dataflow_type: push,pull
  - interface_type: corba_cdr,direct,shared_memory
```

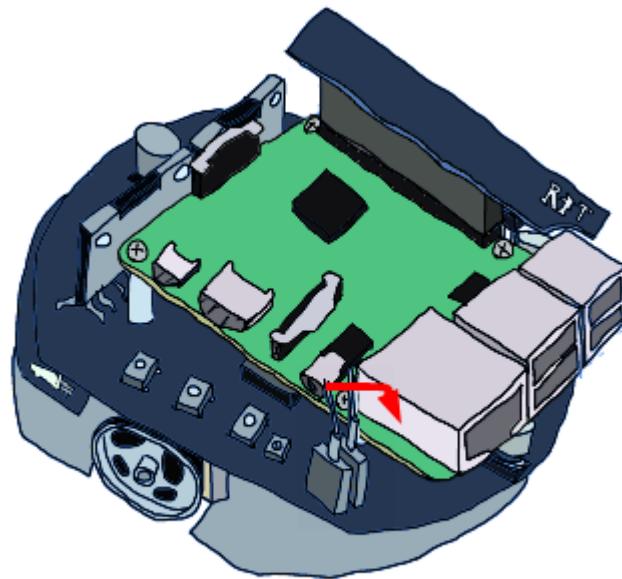
ポートの接続

- RobotController0とRaspberryPiMouseRTC0を接続する



動作確認

- モーターの電源投入
 - 外側のスイッチをONにする



- RTCをアクティブ化して動作確認

リセット

- RTCがエラー状態に遷移した場合にエディタ上には赤く表示される。



```
RTC::ReturnCode_t Test::onActivated(RTC::UniqueId ec_id) {  
    HANDLE hCom = INVALID_HANDLE_VALUE;  
    hCom = CreateFile("COM5", GENERIC_READ | GENERIC_WRITE, 0, NULL, OPEN_EXISTING, 0, NULL);  
    if (hCom == INVALID_HANDLE_VALUE)  
    {  
        return RTC::RTC_ERROR;  
    }
```

例えばonActivated関数で初期化(この例ではCOMポートの初期化)に失敗した場合はRTC_ERRORを返すようにしておけば、初期化に失敗した場合にエラー状態に遷移する

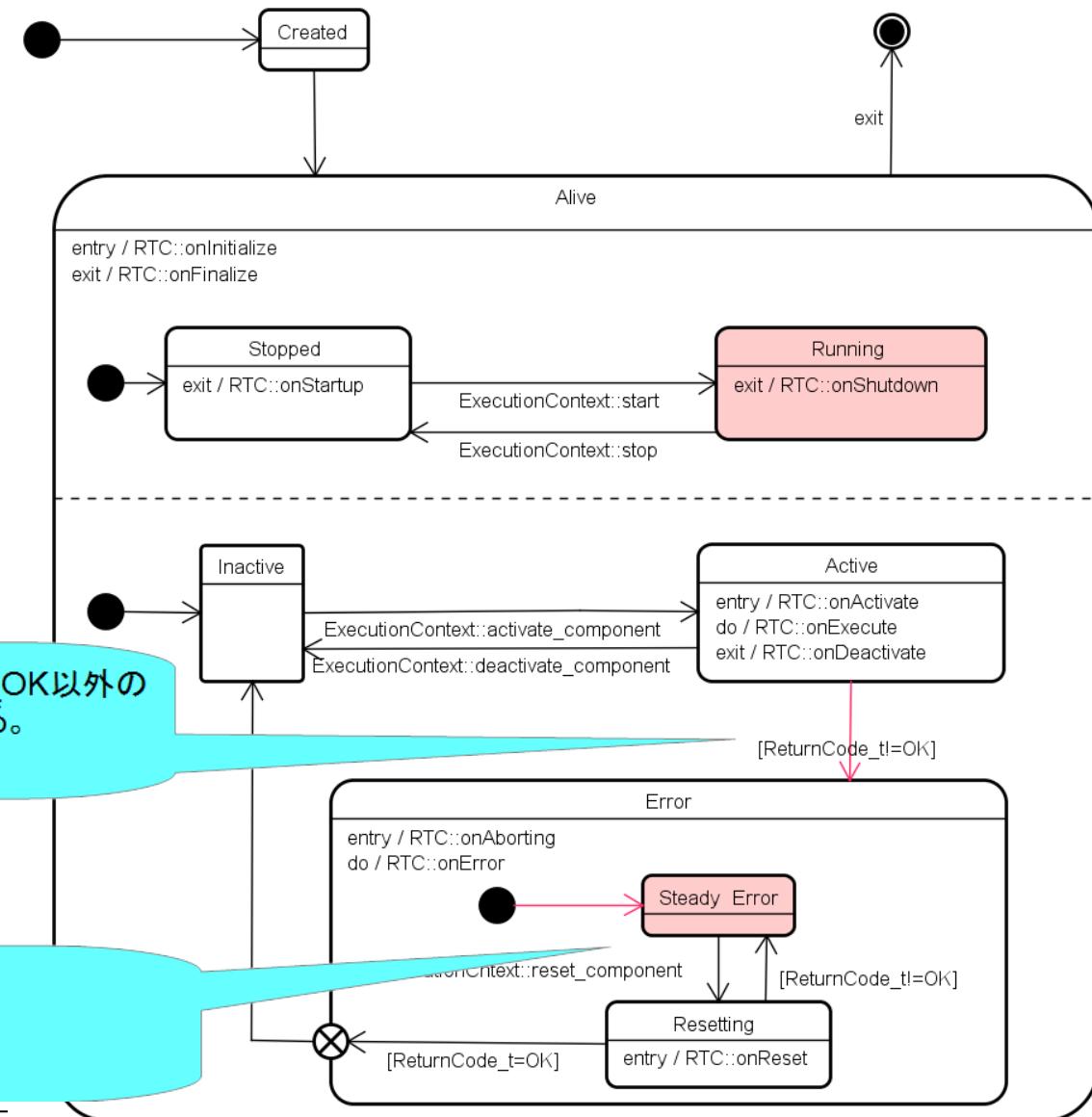
- 以下の操作で非アクティブ状態に戻す



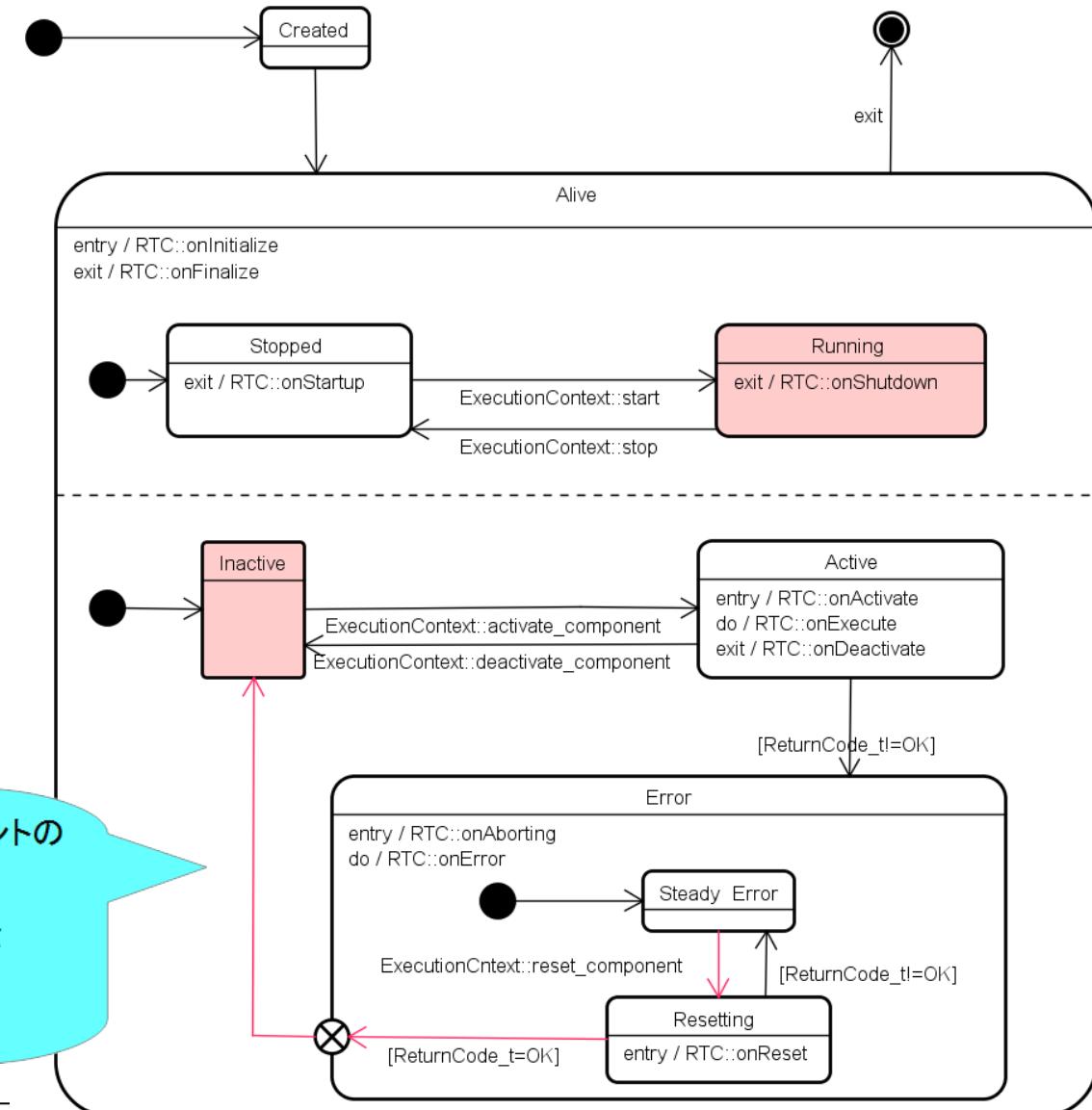
RTCを右クリックしてResetを選択



RTコンポーネントの状態遷移(エラー)



RTコンポーネントの状態遷移(リセット)



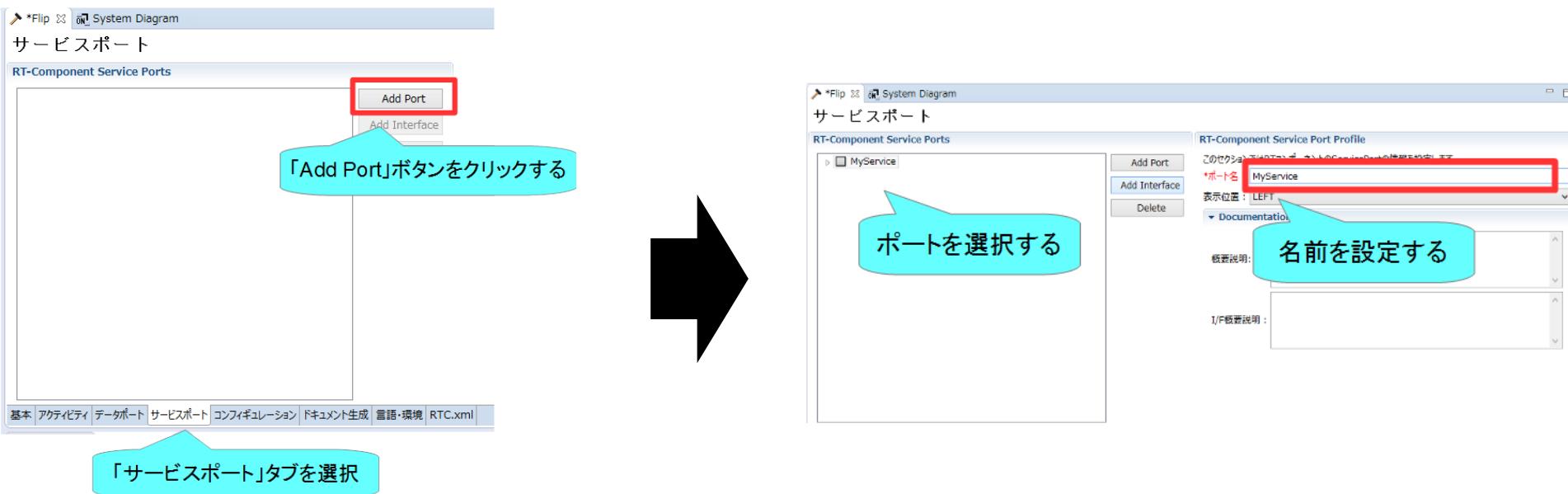
RTシステムエディタの操作によりRTコンポーネントのリセットを行うと`reset_component`メソッドが呼び出される。
`reset_component`メソッドによりコンポーネントが`Inactive`状態に遷移する。
この時`onReset`コールバックが実行される

RTC Builder

補足

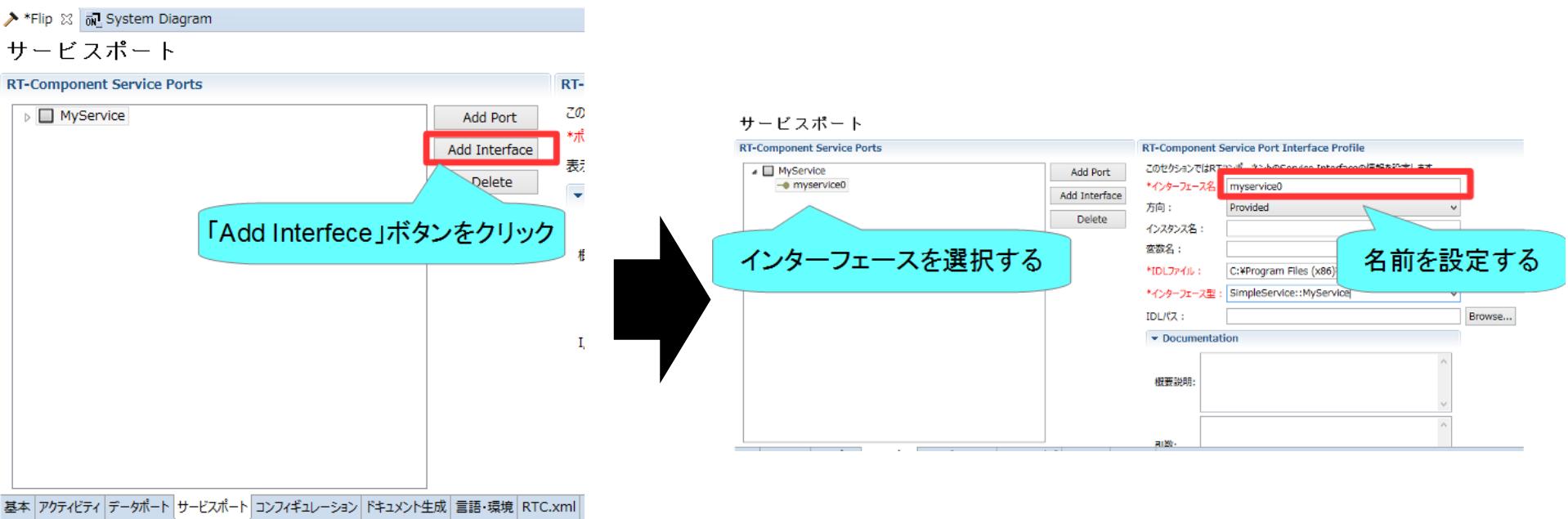
サービスポートの設定

- サービスポートの追加、インターフェースの追加、設定を行う



サービスポートの設定

- インターフェースを追加する



サービスポートの設定

- インターフェースの設定を行う

「Provided」・「Required」から選択
Provided: サービスを提供する側
Required: サービスを利用する側

このセクションではRTコンポーネントのService Interfaceの情報を設定します。

*インターフェース名 : myservice0

方向 : Provided

インスタンス名 :

変数名 :

*IDLファイル : C:\Program Files (x86)\OpenRTM-aist\1.1.2\Com\SimpleService\MyService.idl

*インターフェース型 : SimpleService::MyService

IDLパス :

インターフェース型を選択

「Browse...」をクリックしてIDLファイルを選択

IDLファイルが別のIDLファイルをインクルードしている場合にIDLパスを設定

The diagram illustrates the relationship between service interface types and their providers/consumers. It shows two main components: 'Required Interface' (Consumer) and 'Provided Interface' (Provider). The consumer side is represented by a dashed circle containing a 'ソケット' (Socket) icon, labeled '機能を使う側' (Side that uses the function). The provider side is represented by a dashed circle containing a 'ロリポップ' (Ripple) icon, labeled '機能を提供する側' (Side that provides the function).

- コード生成後、Pythonの場合は idlcompile.bat(idlcompile.sh)を起動する



2016/07/03 18:07 Windows J

2016/07/03 18:07 SH ファイル

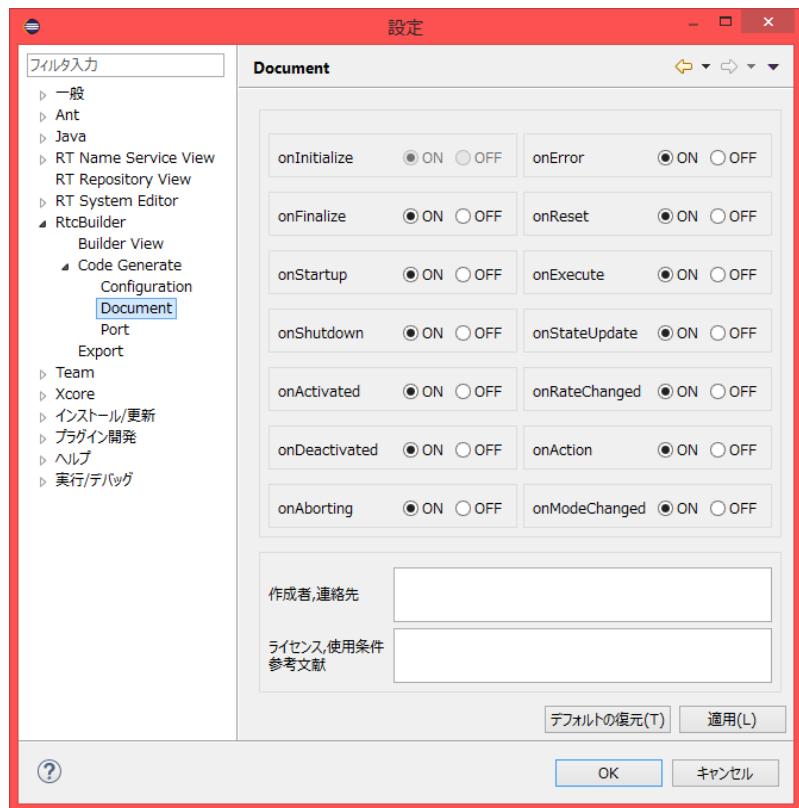
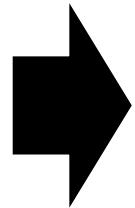
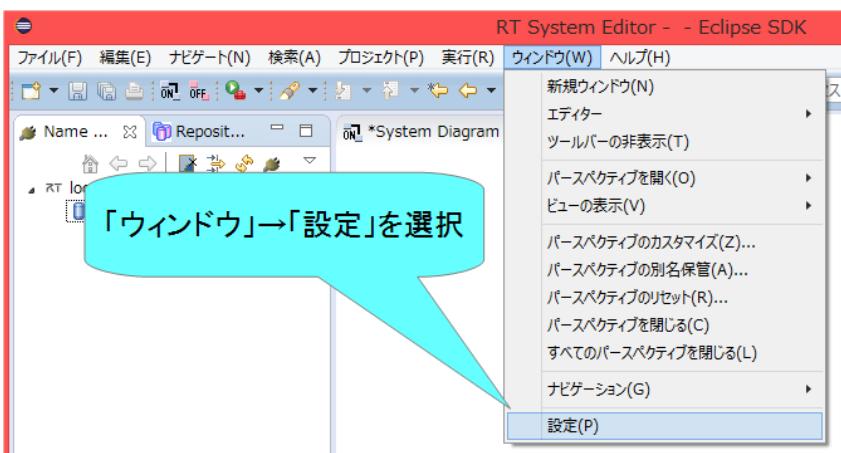
サービスポートの設定

- IDLファイルについて
 - プログラミング言語に非依存のインターフェース定義言語

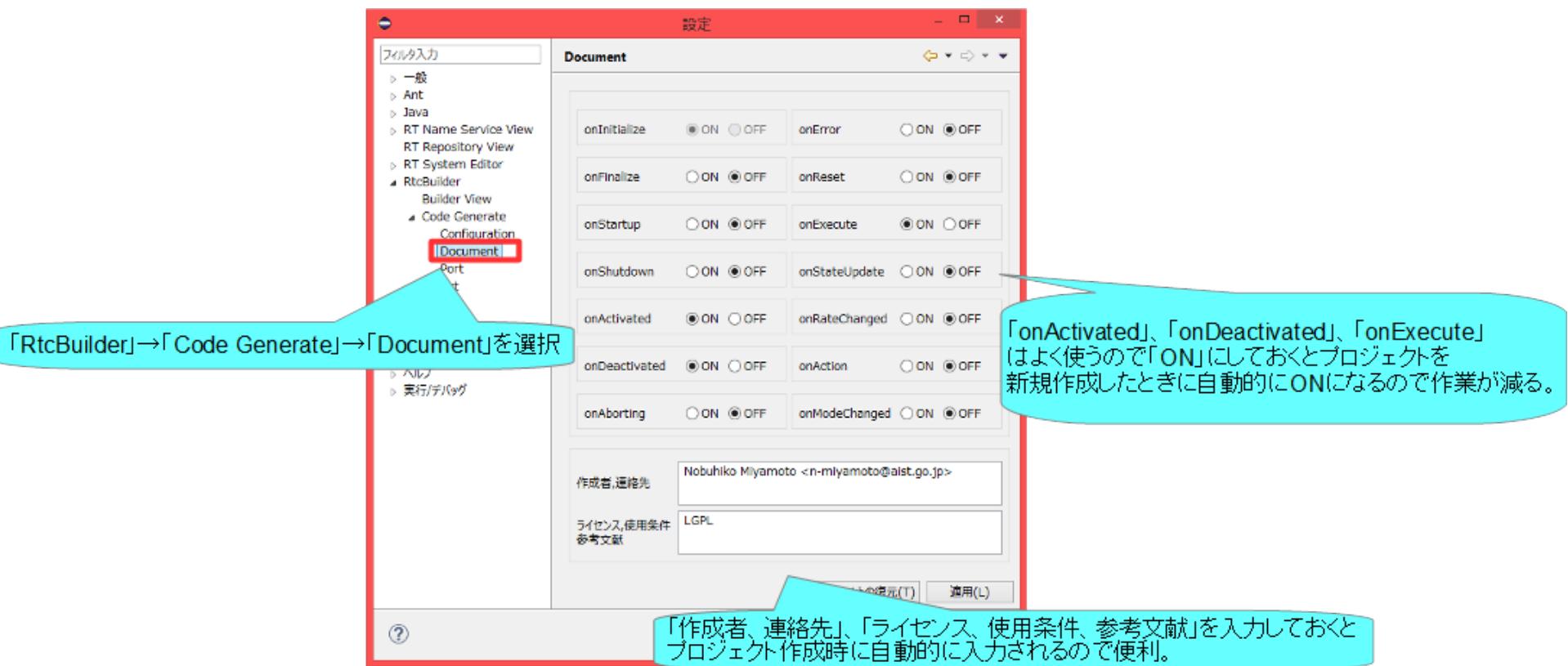
```
1 module SimpleService { ↓
2     typedef sequence<string> EchoList; ↓
3     typedef sequence<float> ValueList; ↓
4     interface MyService ↓
5     { ↓
6         string echo(in string msg); ↓
7         EchoList get_echo_history(); ↓
8         void set_value(in float value); ↓
9         float get_value(); ↓
10        ValueList get_value_history(); ↓
11    }; ↓
12 };
```

- コンシュマー側でプロバイダ側のecho、get_valueなどのオペレーションを呼び出す

RTC Builderに関する設定



RTC Builderに関する設定



独自のデータ型の利用

- 独自のデータ型でデータポートの通信を行う手順
 - IDLファイルを作成する
 - MyDataType.idlを任意のフォルダ(ここではC:\UserDefType)作成

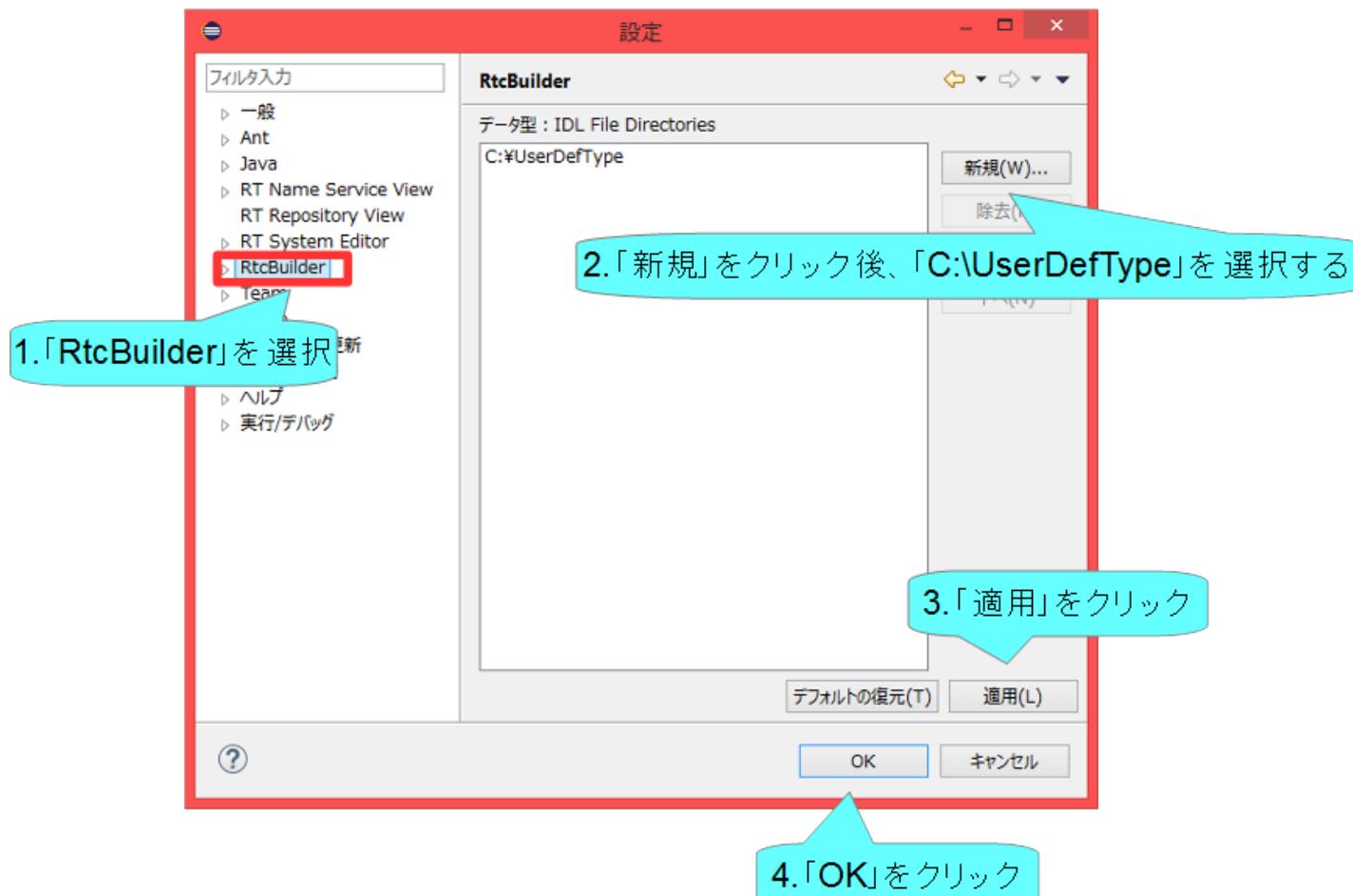
```
1 // @file MyDataType.idl↓
2 #include "BasicDataType.idl"↓
3 ↓
4 struct MyData↓
5 {↓
6     RTC::Time tm;↓
7     short shortVariable;↓
8     long longVariable;↓
9     sequence<double> data;↓
10 } ;[EOF]
```

- 別のIDLファイルをインクルードしている場合は同じフォルダにコピーする

| Windows 8... > UserDefType | | | UserDefTypeの検索 |
|----------------------------|------------------|----------|----------------|
| 名前 | 更新日時 | 種類 | |
| BasicDataType.idl | 2014/08/28 20:06 | IDL ファイル | |
| MyDataType.idl | 2016/07/03 18:57 | IDL ファイル | |

独自のデータ型の利用

- 独自のデータ型でデータポートの通信を行う手順
 - RTC Builderの設定でIDLファイルの存在するディレクトリを追加



独自のデータ型の利用

- 独自のデータ型でデータポートの通信を行う手順

このセクションではRTコンポーネントのDataPort(データポート)の情報を設定します。

| | | | | | |
|----------------|----|--------|-----------------|-----|--------|
| *ポート名 (InPort) | in | Add | *ポート名 (OutPort) | out | Add |
| < > | | Delete | < > | | Delete |

このセクションではデータポート毎の概要を説明するドキュメントを記述します。
上のデータポートを選択すると、それぞれのドキュメントが記述できます。

ポート名 :

*データ型

変数名

表示位置

Document

Document

Document

デーティ型一覧にMyDataが追加

RT System Editor

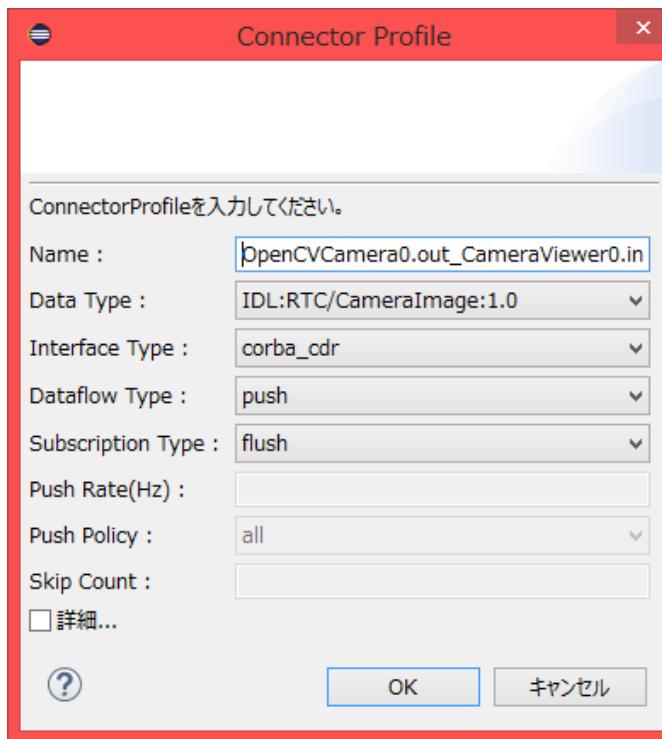
補足

コネクタプロファイルの設定

| 項目 | 設定内容 |
|------------------|--|
| Name | 接続の名称 |
| DataType | ポート間で送受信するデータの型. ex)TimedOctet, TimedShortなど |
| InterfaceType | データを送信方法. ex)corba_cdrなど |
| DataFlowType | データの送信手順. ex)push, pullなど |
| SubscriptionType | データ送信タイミング. 送信方法がPushの場合有効. New, Periodic, Flushから選択 |
| Push Rate | データ送信周期(単位:Hz). SubscriptionTypeがPeriodicの場合のみ有効 |
| Push Policy | データ送信ポリシー. SubscriptionTypeがNew, Periodicの場合のみ有効. all, fifo, skip, newから選択 |
| Skip Count | 送信データスキップ数. Push PolicyがSkipの場合のみ有効 |

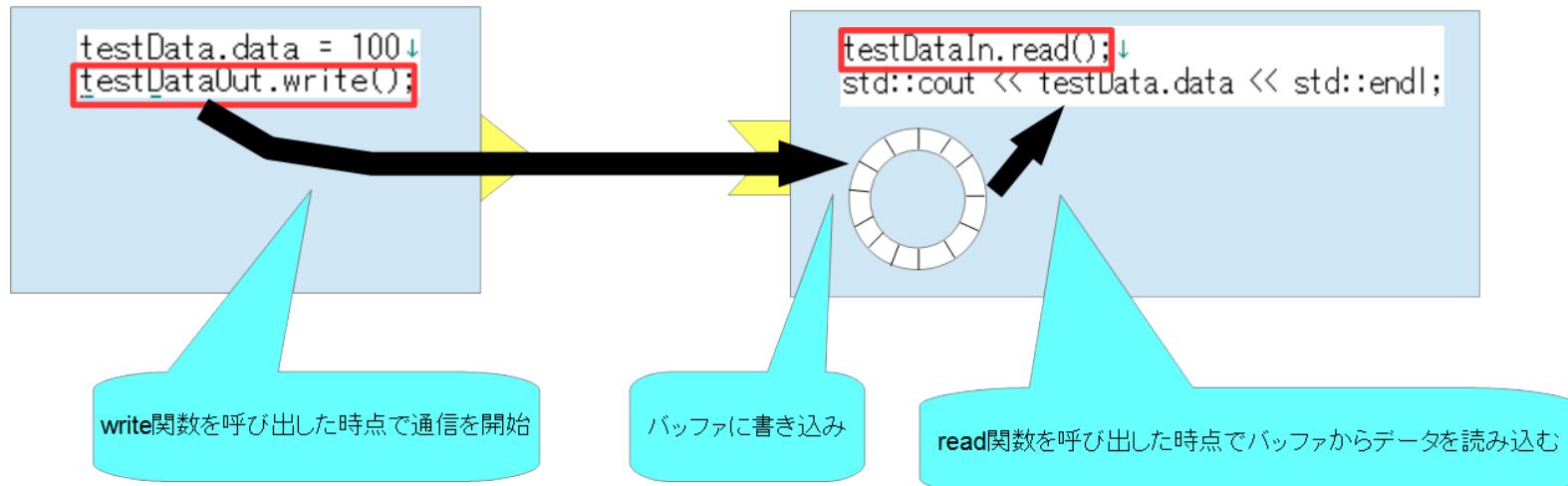
コネクタプロファイルの設定

- InterfaceType
 - データの送信方法
 - 1.1.2ではcorba_cdr(CORBAによる通信)のみ選択可能
 - 1.2.0では以下の通信方法も選択可能になる予定
 - direct(同一プロセスで起動したRTC間でデータを直接変数に渡す)
 - shared_memory(共有メモリによる通信)
- DataFlowType
 - データの送信手順
 - Push
 - OutPortがInPortにデータを送る
 - Pull
 - InPortがOutPortに問い合わせてデータを受け取る
- SubscriptionType
 - データ送信タイミング(DataFlowTypeがPush型のみ有効)
 - flush(同期)
 - バッファを介さず即座に同期的に送信
 - new(非同期)
 - バッファ内に新規データが格納されたタイミングで送信
 - periodic(非同期)
 - 一定周期で定期的にデータを送信
- Push Policy(SubscriptionTypeがnew、periodicのみ有効)
 - データ送信ポリシー
 - all
 - バッファ内のデータを一括送信
 - fifo
 - バッファ内のデータをFIFOで1個ずつ送信
 - skip
 - バッファ内のデータを間引いて送信
 - new
 - バッファ内のデータの最新値を送信(古い値は捨てられる)

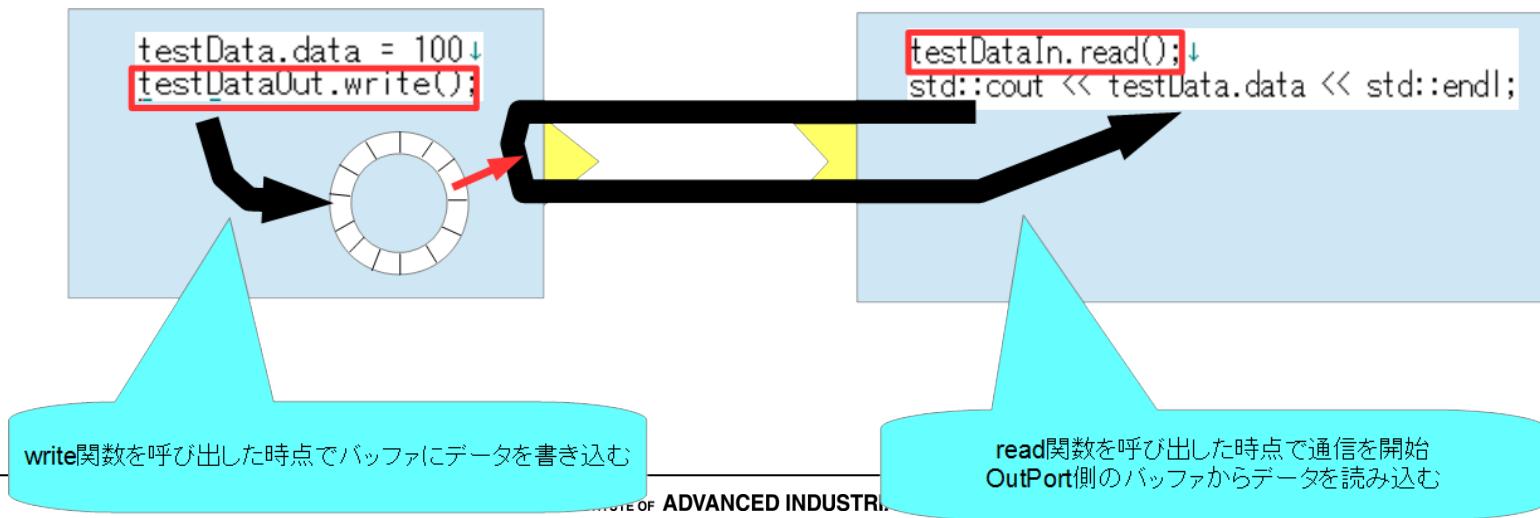


コネクタプロファイルの設定

- DataFlowType
 - Push

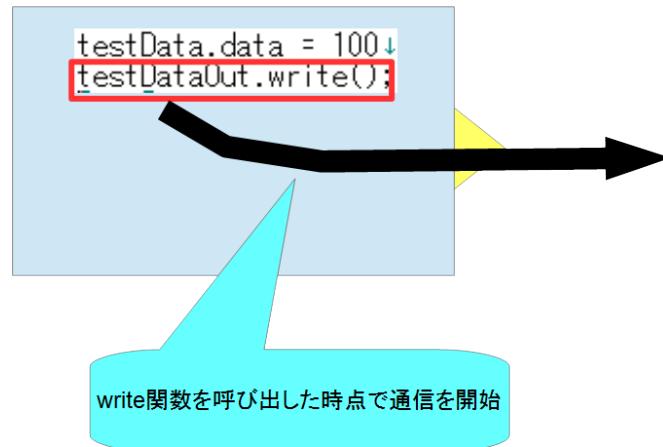


- Pull

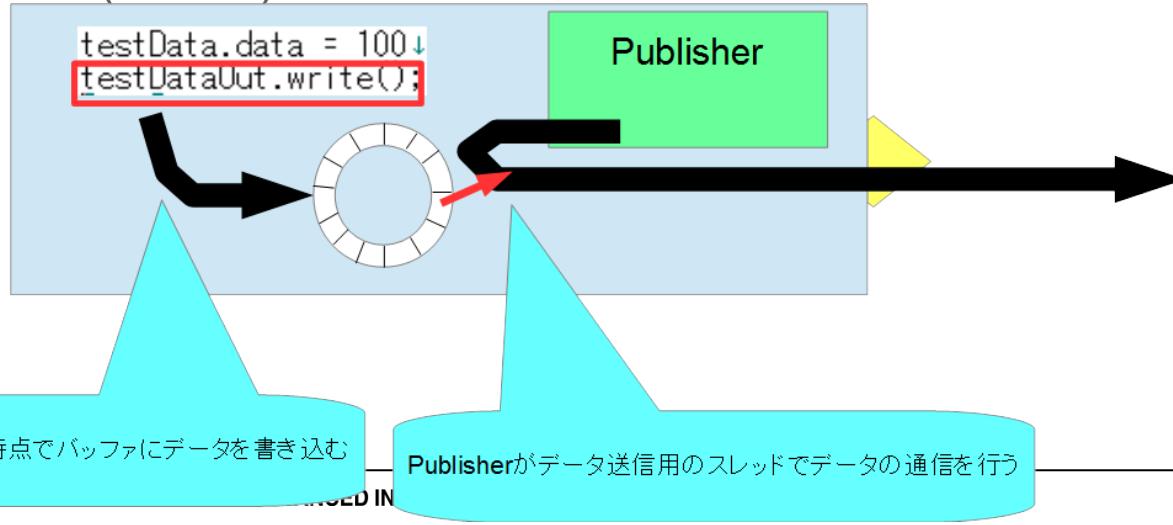


コネクタプロファイルの設定

- SubscriptionType
 - flush(同期)

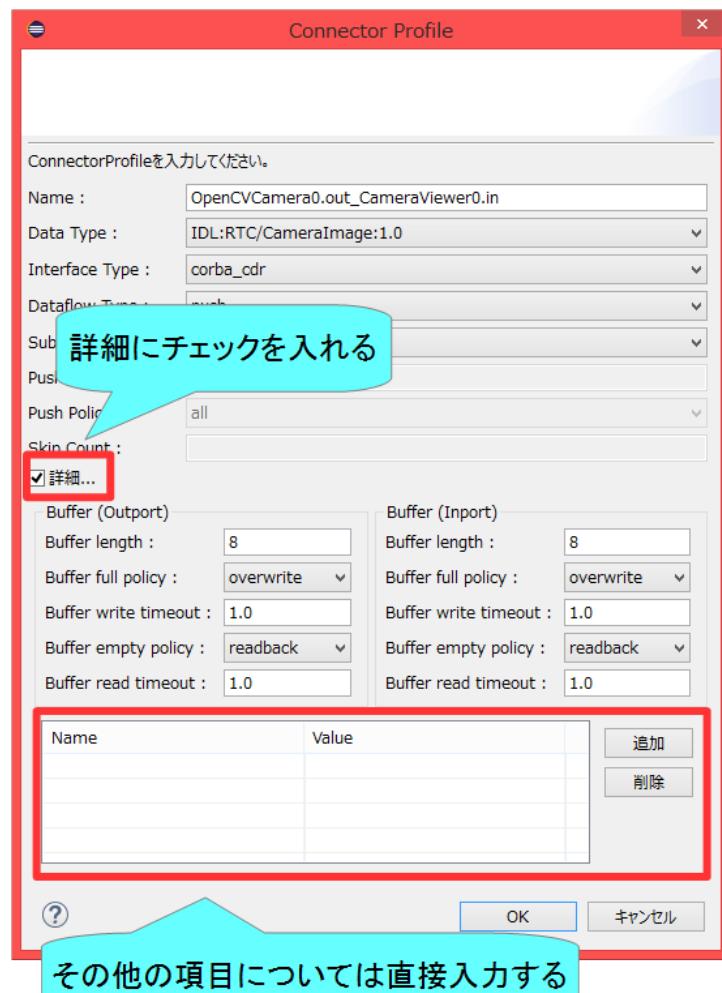


- new、periodic(非同期)



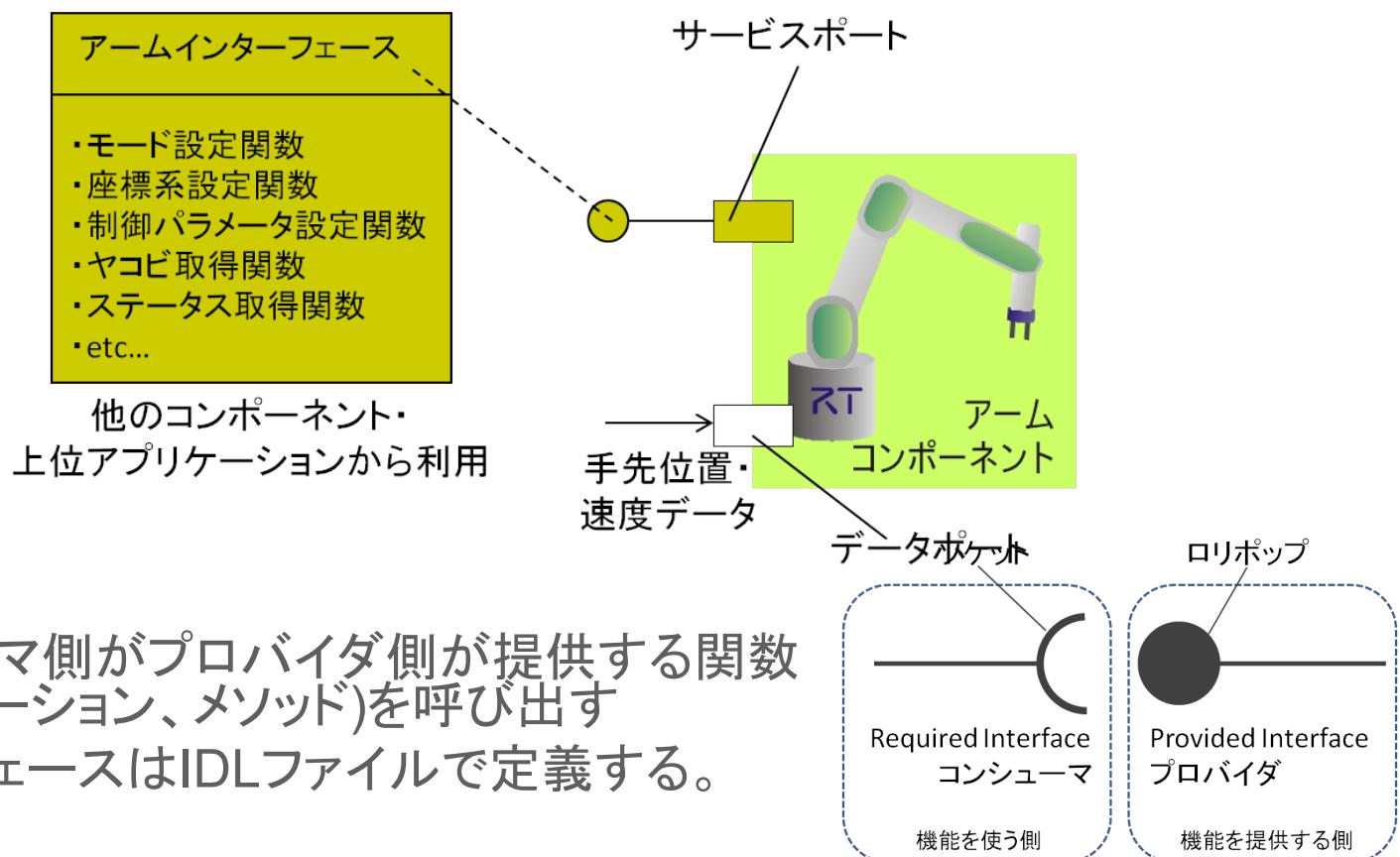
コネクタプロファイルの設定

| 項目 | 設定内容 |
|----------------------|---|
| Buffer length | バッファの大きさ |
| Buffer full policy | データ書き込み時に、バッファフルだった場合の処理。overwrite, do_nothing, blockから選択 |
| Buffer write timeout | データ書き込み時に、タイムアウトイベントを発生させるまでの時間(単位:秒) |
| Buffer empty policy | データ読み出し時に、バッファが空だった場合の処理。readback, do_nothing, blockから選択 |
| Buffer read timeout | データ読み出し時に、タイムアウトイベントを発生させるまでの時間(単位:秒) |



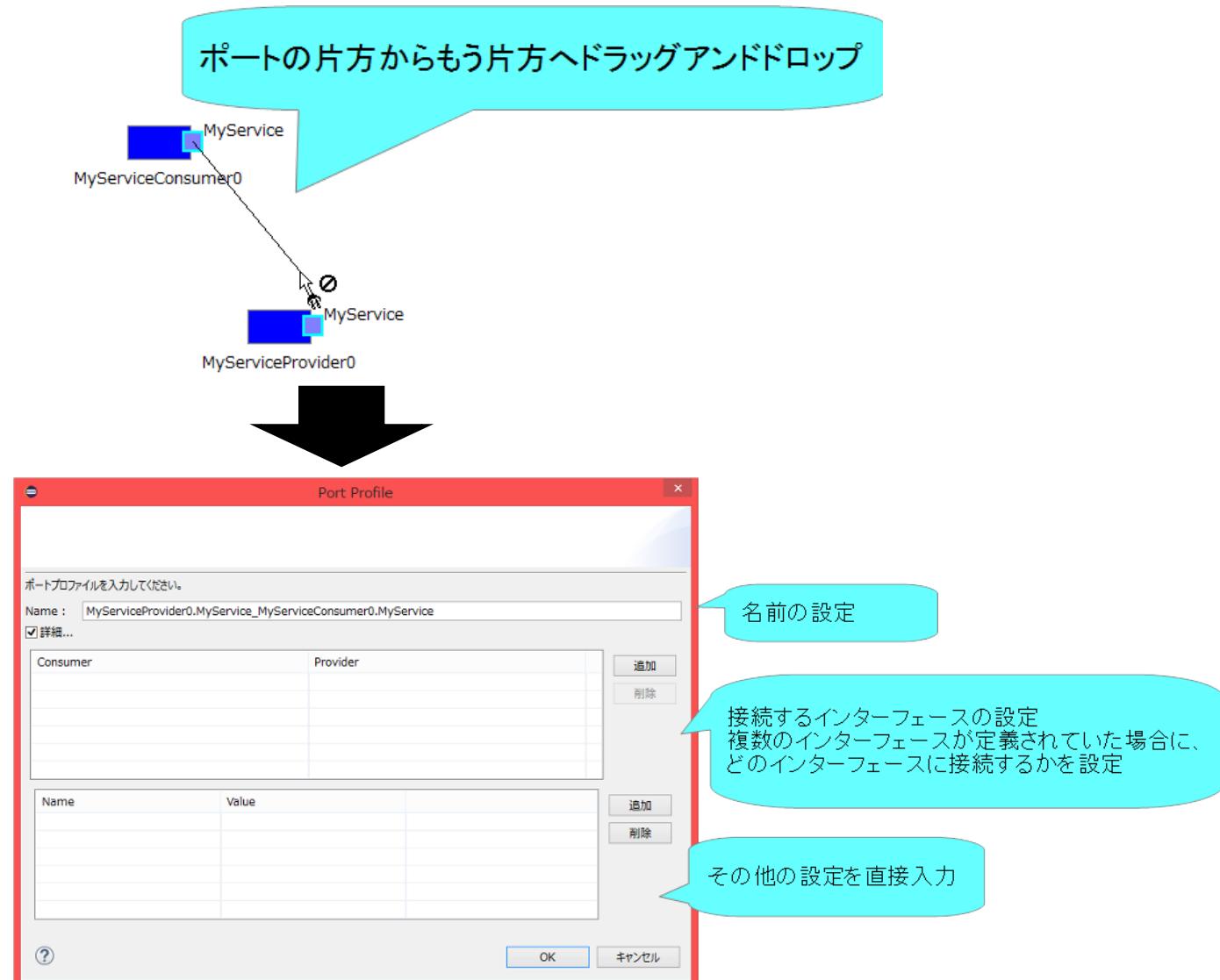
サービスポートについて

- コマンドレベルのやり取りを行うための仕組み
 - 任意のタイミングで操作を行いたい時などに使用
 - 例えばロボットアームのサーボを停止させる、ハンドを閉じる等



- コンシューマ側がプロバイダ側が提供する関数群(オペレーション、メソッド)を呼び出す
- インターフェースはIDLファイルで定義する。

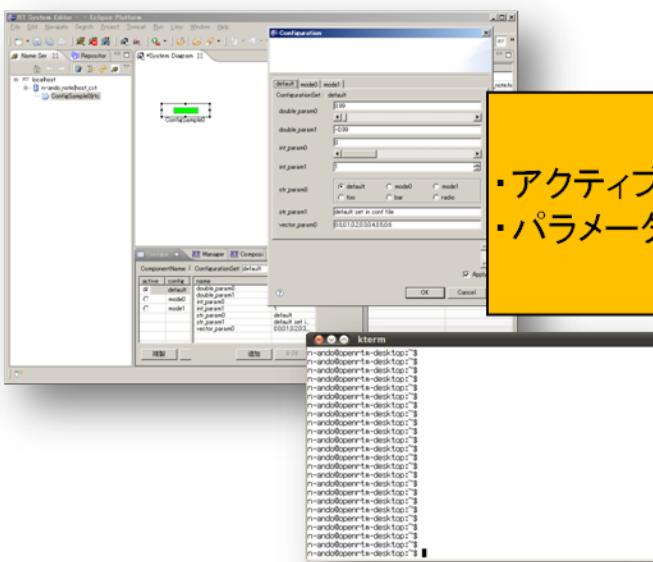
サービスポートの接続



コンフィギュレーションパラメータについて

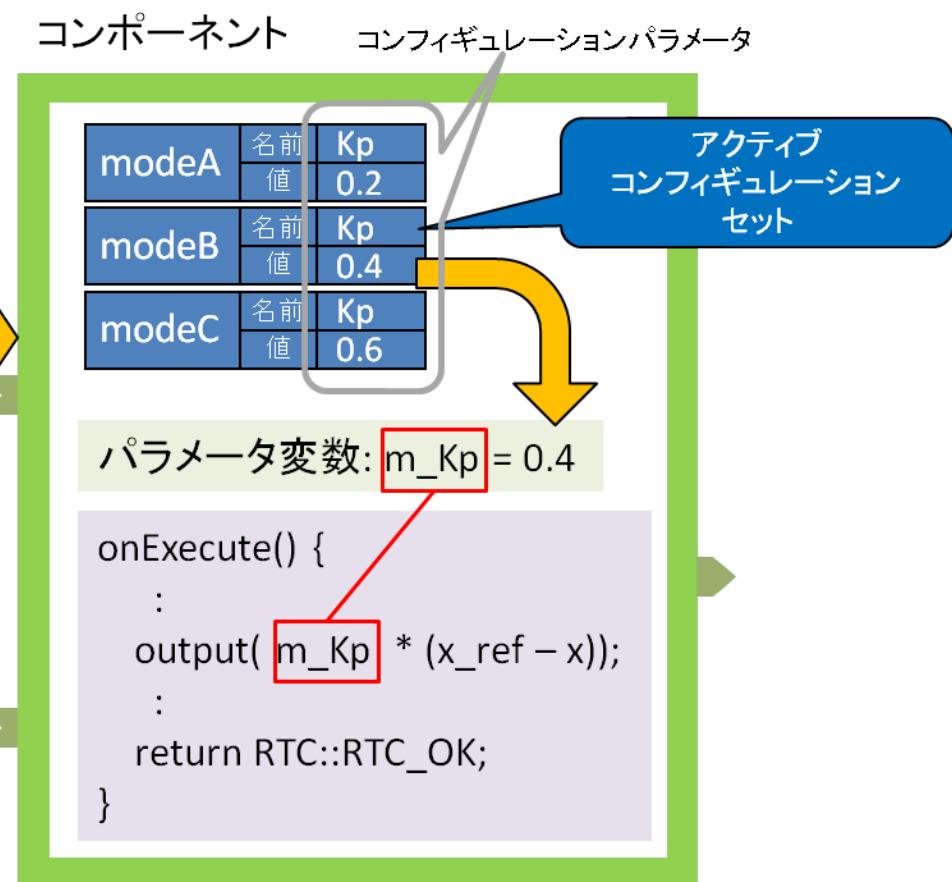
- パラメータを外部から操作する仕組み
 - コンポーネント作成後に変更が必要なパラメータを設定する
 - 例えばデバイスが接続されているCOMポート番号の設定等

ツール・アプリケーション



- アクティブセットの変更
- パラメータ値の変更

ツール・アプリケーションから、コンポーネント内部で使用する変数の値を変更できる。



コンフィギュレーションパラメータの設定

対象のRTCをクリックすると表示

「Configuration View」タブを選択

パラメーター覧

ComponentName: ConfigSample0 ConfigurationSet: default

| active | config |
|----------------------------------|---------|
| <input checked="" type="radio"/> | default |
| <input type="radio"/> | mode0 |
| <input type="radio"/> | mode1 |

| name | value |
|---------------|----------|
| double_param0 | 0.99 |
| double_param1 | -0.99 |
| int_param0 | 0 |
| int_param1 | 1 |
| str_param0 | default |
| str_param1 | defau... |
| vector_param0 | 0.0,0... |

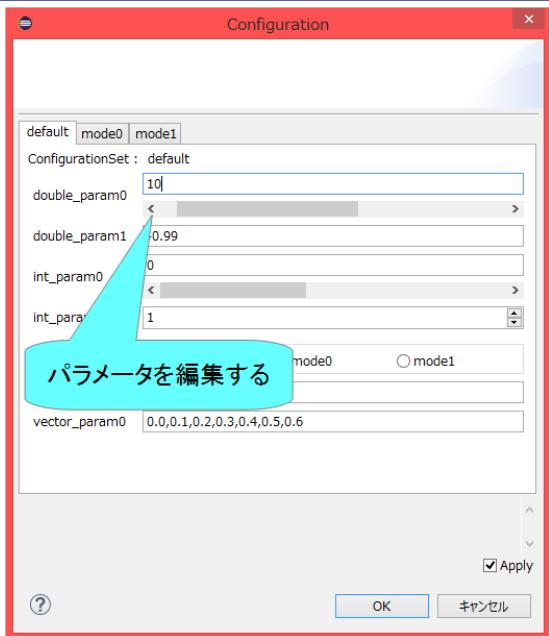
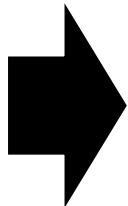
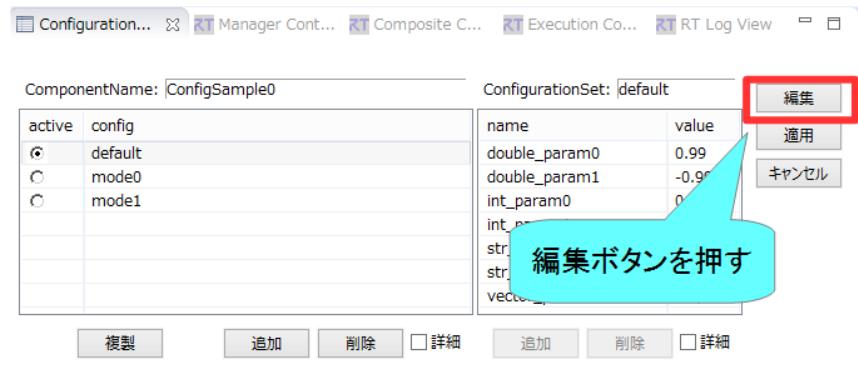
コンフィギュレーションセット一覧

複製 追加 削除 □ 詳細 追加 削除 □ 詳細

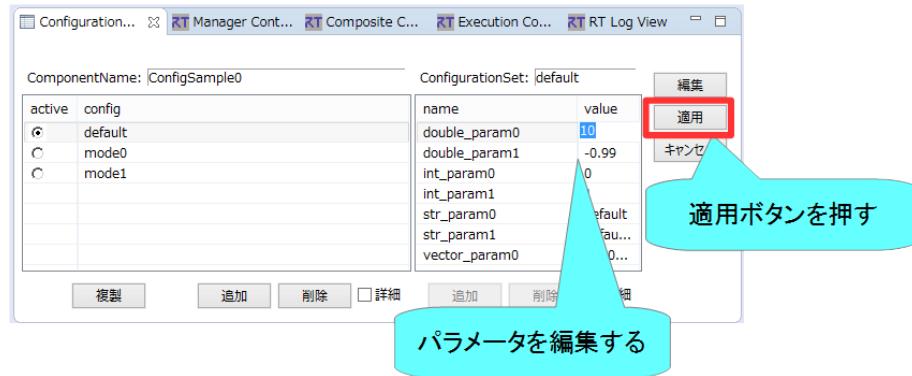
編集 適用 キャンセル

コンフィギュレーションパラメータの設定

- 方法1

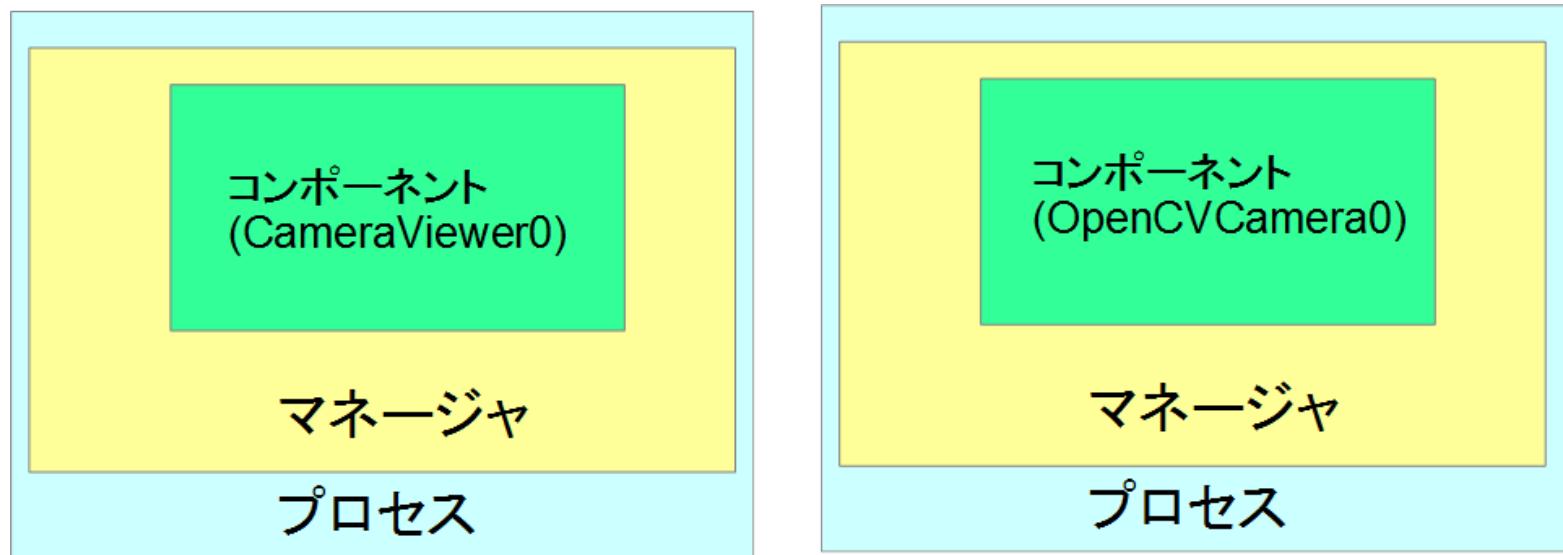


- 方法2



マネージャの操作

- CameraViewerComp.exe、OpenCVCameraComp.exeのプロセスではマネージャが起動している
 - マネージャがコンポーネントを起動する

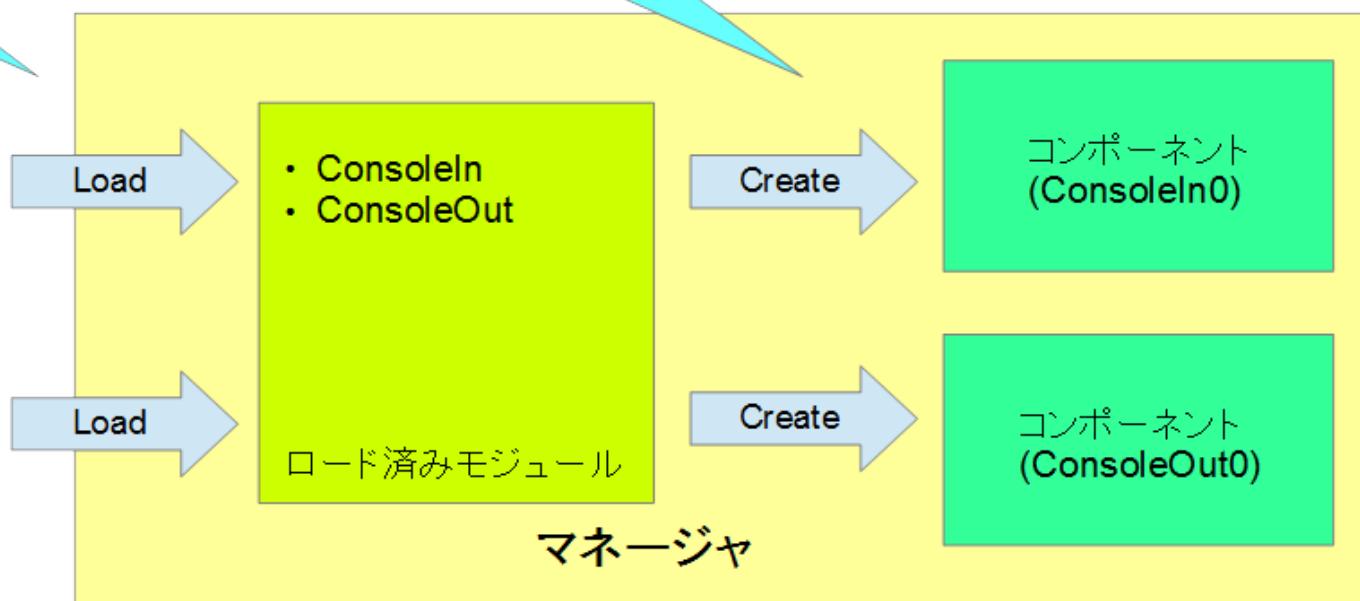


基本的にマネージャは各プロセスに1つ起動する。
マネージャがコンポーネントを起動する

マネージャの操作

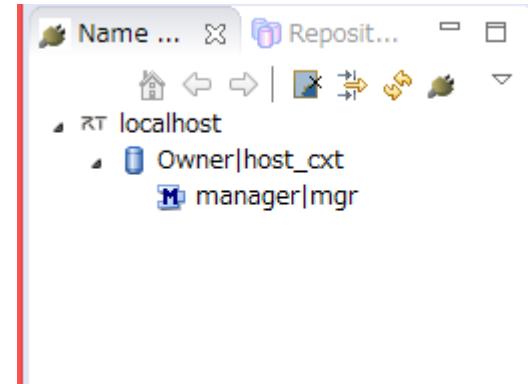
1. モジュールをロードする
 - ・C++:.dll、.so
 - ・Python:.py
 - ・Java:.jar

2. コンポーネントを起動する



マネージャの操作

- マスターマネージャの起動、RT System Editorからの操作によるRTCの生成までの手順を説明する
 - rtc.confの設定
 - 「manager.is_master」を「YES」に設定して起動するマネージャをマスターに設定する
 - manager.is_master: YES
 - モジュール探索パスの設定
 - manager.modules.load_path: .., C:¥¥Program Files (x86)¥¥OpenRTM-aist¥¥1.1.2¥¥Components¥¥C++¥¥Examples¥¥vc12
 - 作成した rtc.conf を設定ファイルの指定して rtcd.exe を起動する
 - rtcd は コマンドプロンプトから rtcd.exe を入力するか、OpenRTM-aist をインストールした フォルダ から コピー して 使用する
 - rtcd は マネージャの起動のみを行う
 - ～Comp.exe は 起動時に 特定 の コンポーネント の 起動 も 行う
 - RT System Editor の ネームサービス ビュー に マネージャ が 表示される



マネージャの操作

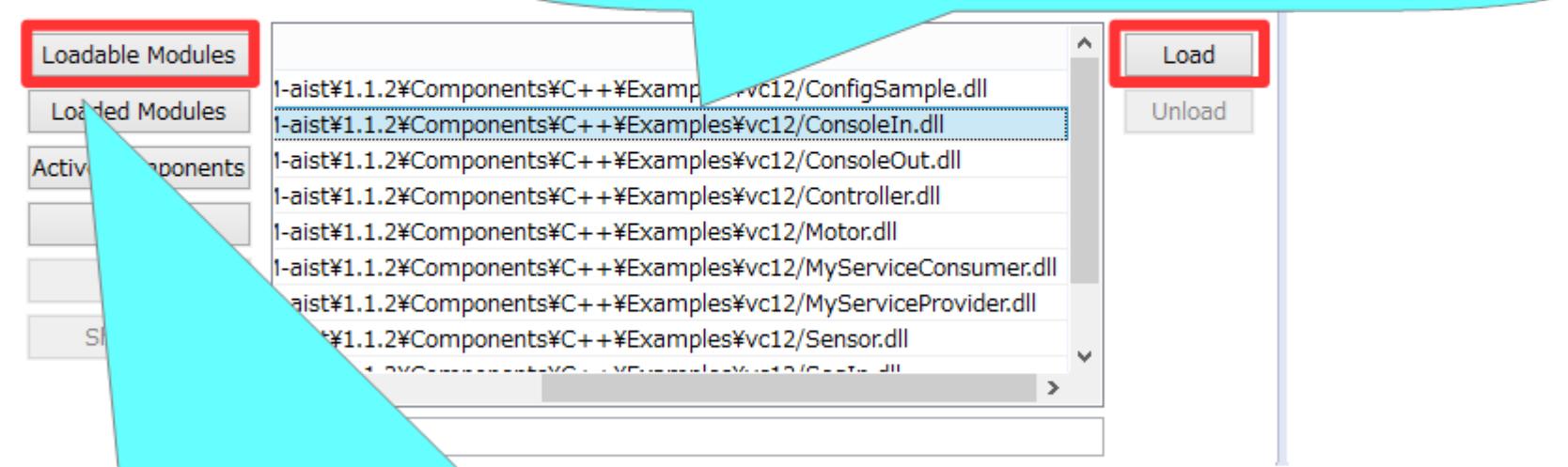
- モジュールのロード

1.「Manager Control View」タブを選択

Configuration... RT Manager Cont... ✎

...

3.ロードするモジュールを選択して「Load」ボタンを押す

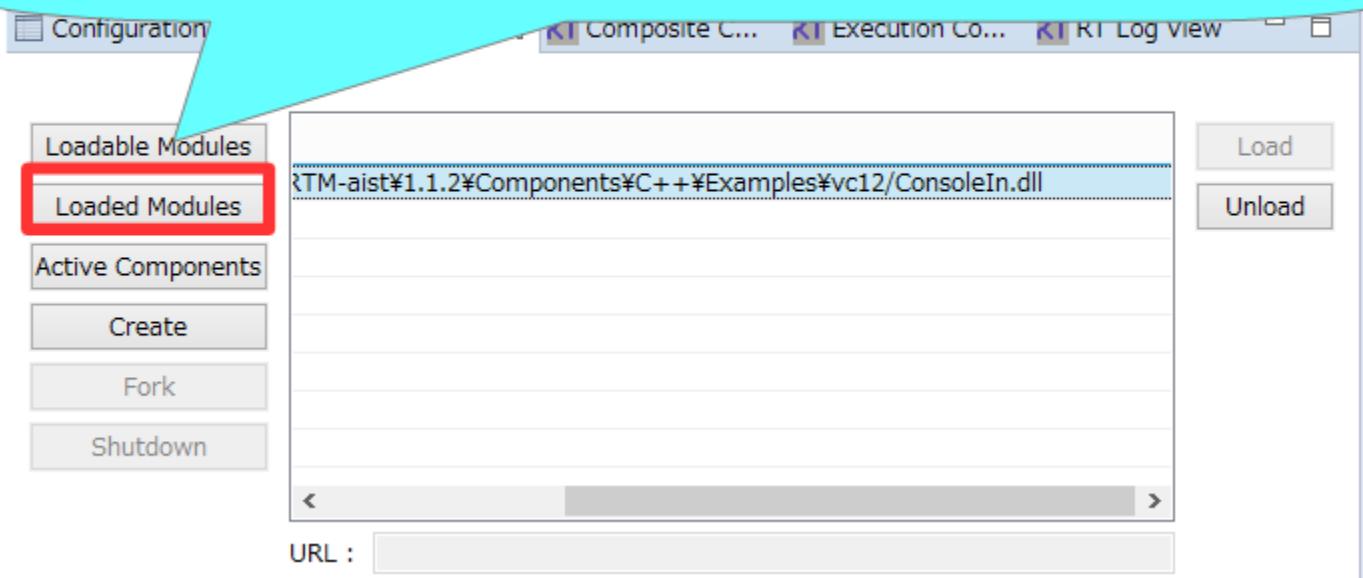


2.「Loadable Modules」ボタンを押すとロード可能なモジュール一覧表示

マネージャの操作

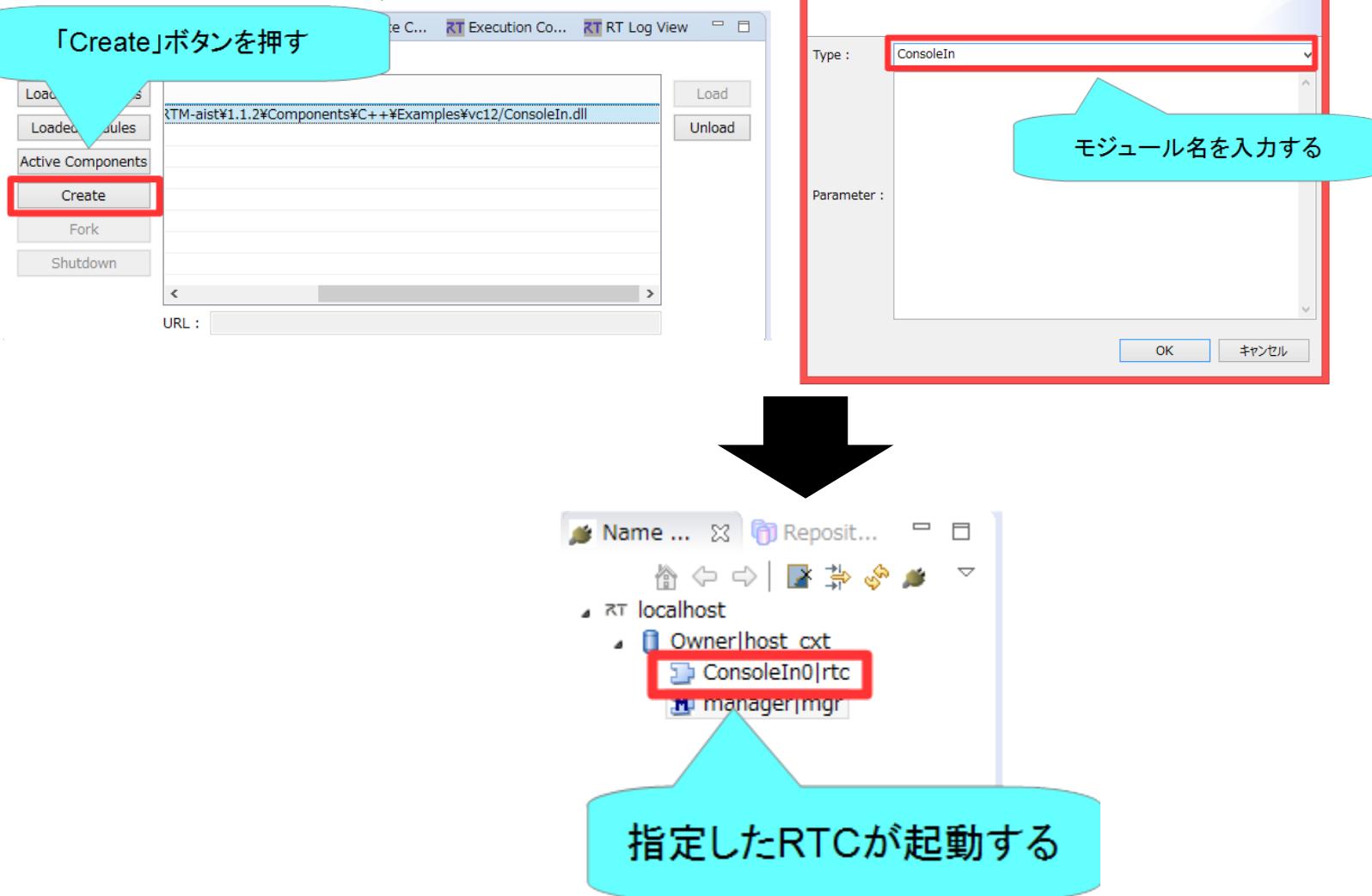
- モジュールのロード

「Loaded Modules」ボタンを押すとロード済みのモジュール一覧表示



マネージャの操作

- RTCの生成



実行コンテキストの操作

RTCをクリック

「Execution Context View」タブを選択

実行周期

関連付けている実行コンテキスト一覧

実行コンテキストの情報

The screenshot shows the RT Manager application window with the following details:

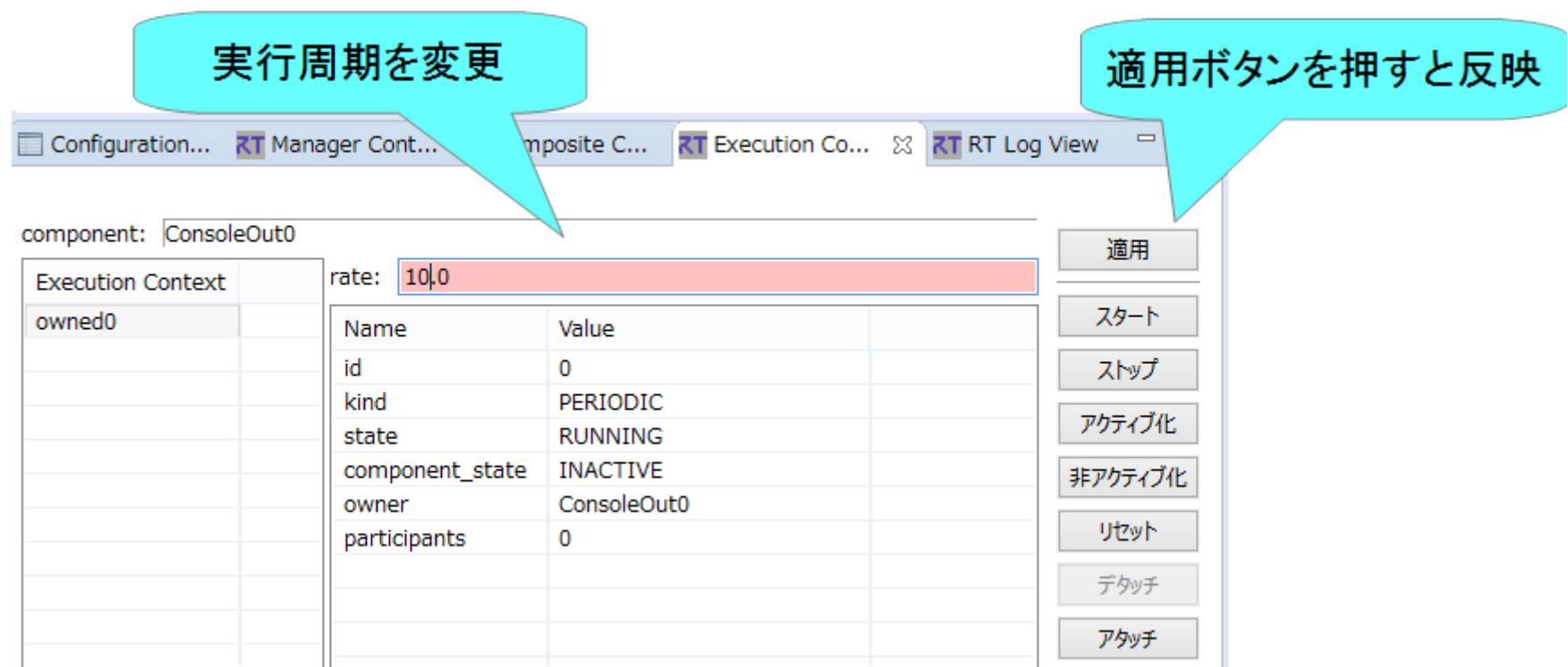
- Top navigation bar: Configuration..., RT Manager Cont..., RT Composite C..., RT Execution Co..., RT Log View.
- Selected tab: RT Execution Co... (highlighted in blue).
- Component selection: component: ConsoleOut0
- Execution Context table:

| Execution Context | |
|-------------------|--|
| owned0 | |
- Rate input field: rate: 1000.0 (highlighted with a red box).
- Table of execution context properties:

| Name | Value |
|-----------------|-------------|
| id | 0 |
| kind | PERIODIC |
| state | RUNNING |
| component_state | INACTIVE |
| owner | ConsoleOut0 |
| participants | 0 |
- Buttons on the right: 適用 (Apply), スタート (Start), 停止 (Stop), アクティビ化 (Activate), 非アクティビ化 (Deactivate), リセット (Reset), デタッチ (Detach), アタッチ (Attach).

実行コンテキストの操作

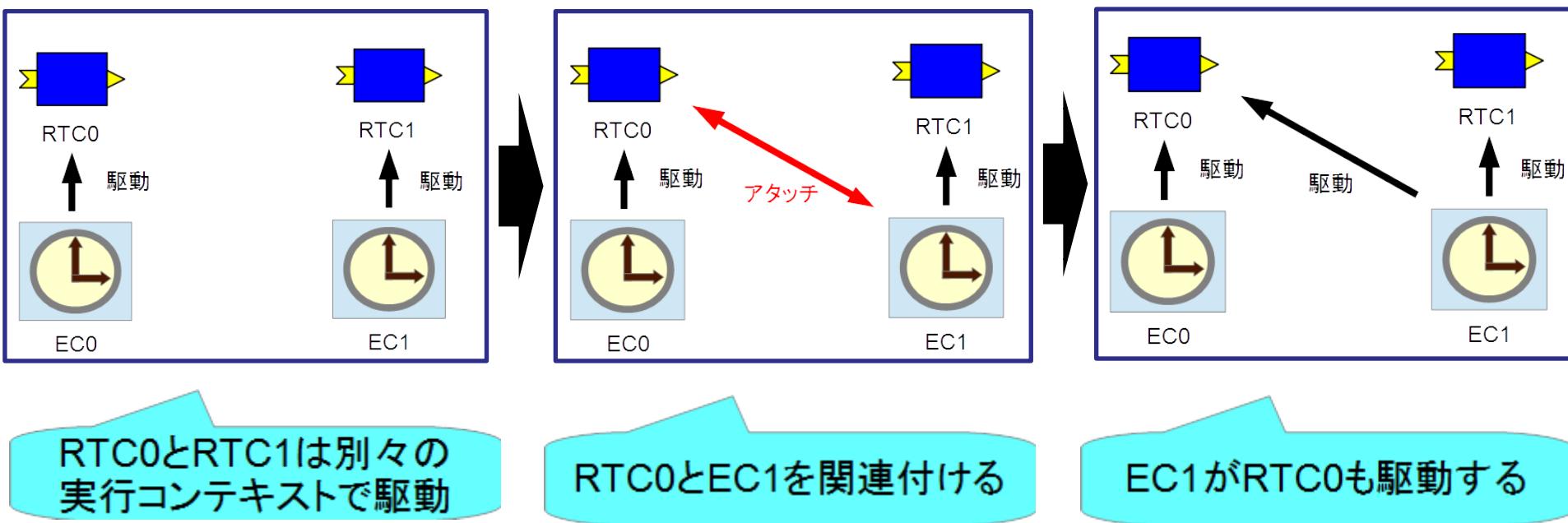
- 実行周期の設定



実行コンテキストの操作

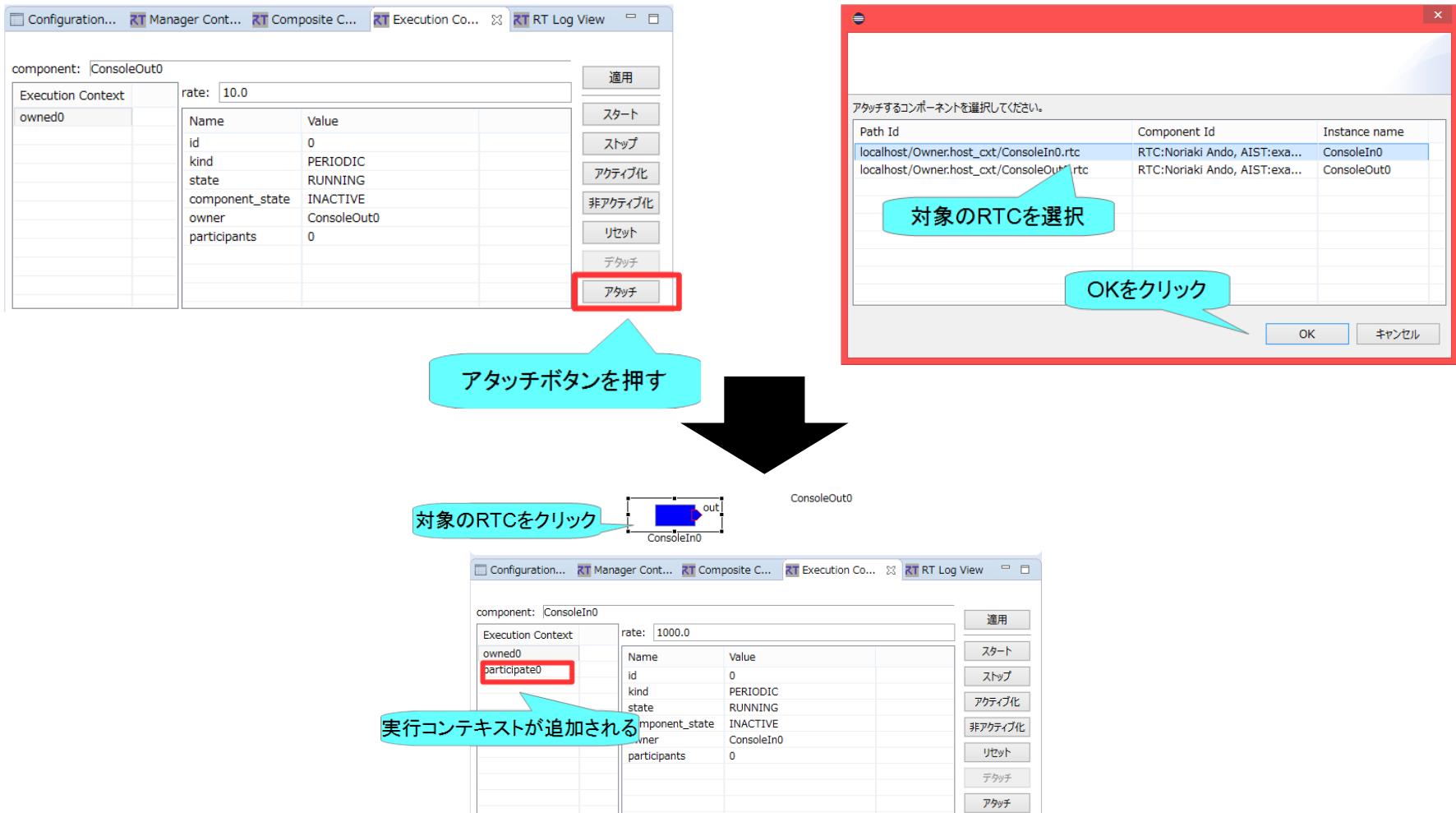
- 実行コンテキストの関連付け

- RTC起動時に生成した実行コンテキスト以外の実行コンテキストと関連付け
 - ・関連付けた実行コンテキストでRTCを駆動させる
- 他のRTCとの実行を同期させる



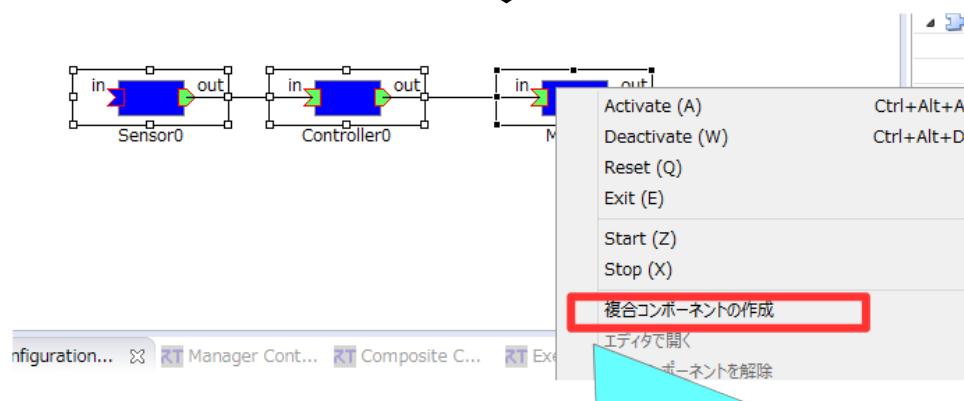
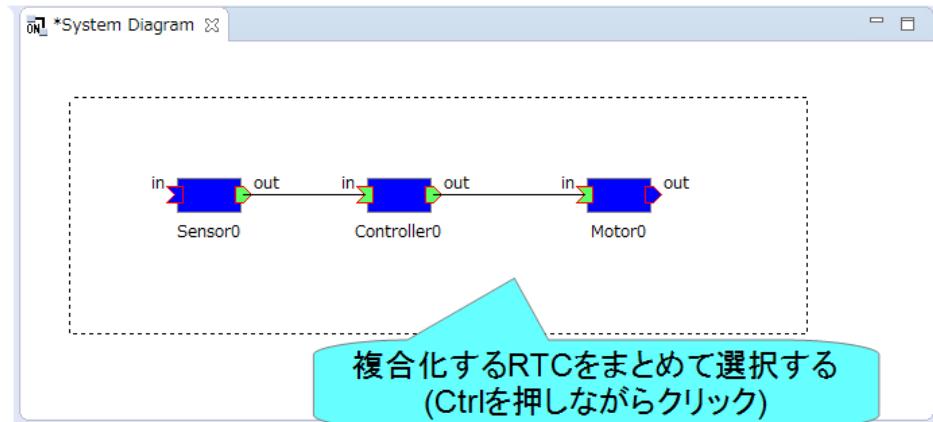
実行コンテキストの操作

- 実行コンテキストの関連付け



複合コンポーネントの操作

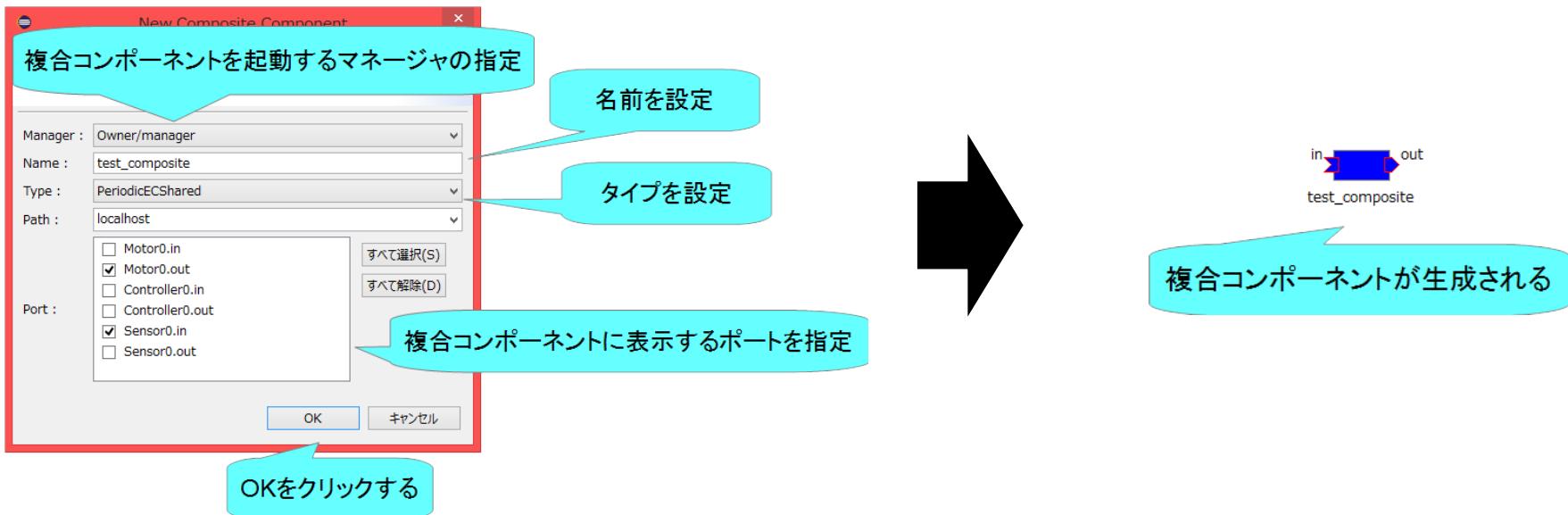
- 複合コンポーネントの生成



右クリックして「複合コンポーネントの作成」を選択

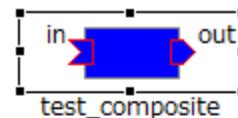
複合コンポーネントの操作

- 複合コンポーネントの生成



- Type
 - 以下の3種類から選択可能
 - PeriodicECShared
 - 実行コンテキストの共有
 - PeriodicStateShared
 - 実行コンテキスト、状態の共有
 - Grouping
 - グループ化のみ

複合コンポーネントの操作



複合コンポーネントをクリック

「Composite Component View」タブを選択

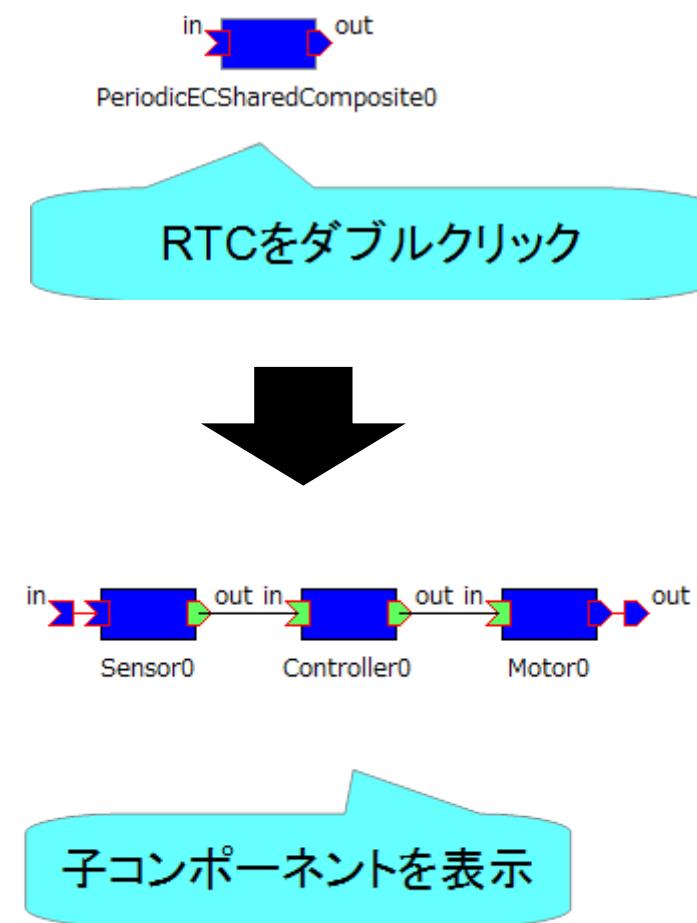
Screenshot of the Composite Component View interface. At the top, there are tabs: Configuration..., Manager Cont..., Composite C..., Execution Co..., RT Log View, and others. Below the tabs, there are input fields for "component" (set to "test_composite") and "type" (set to "PeriodicECShared"). A table lists components and their corresponding ports:

| | component | port |
|-------------------------------------|-------------|-----------------|
| <input type="checkbox"/> | Controller0 | Controller0.in |
| <input type="checkbox"/> | Controller0 | Controller0.out |
| <input checked="" type="checkbox"/> | Sensor0 | Sensor0.in |
| <input type="checkbox"/> | Sensor0 | Sensor0.out |
| <input type="checkbox"/> | Motor0 | Motor0.in |
| <input checked="" type="checkbox"/> | Motor0 | Motor0.out |

On the right side of the table, there are two buttons: "適用" (Apply) and "キャンセル" (Cancel). The "適用" button is highlighted with a red box. A callout bubble points to this button with the text "適用ボタンを押すと変更を反映".

表示するポートの選択

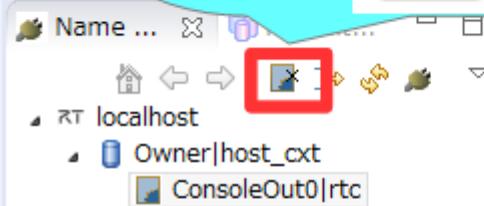
複合コンポーネントの操作



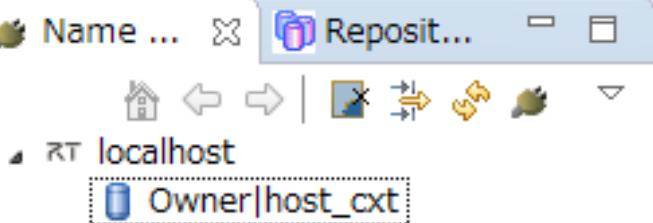
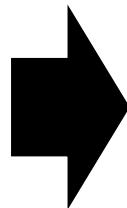
ゾンビの削除

- RTCのプロセスが異常終了する等してネームサーバーにゾンビが残った場合、以下の手順で削除する

ゾンビクリアボタンを押す

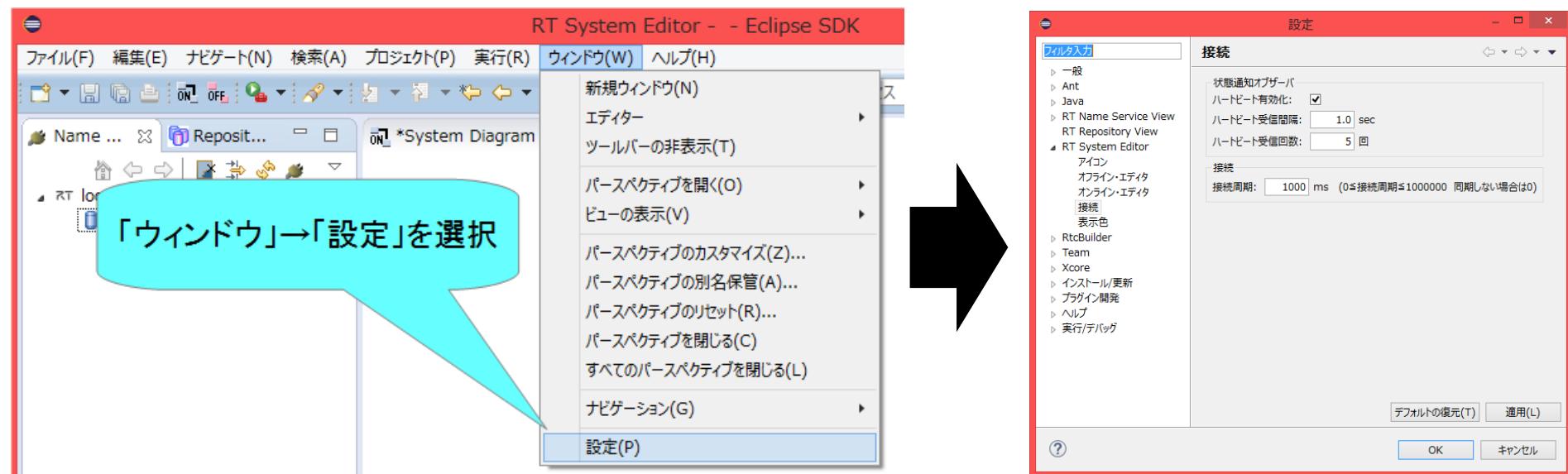


ゾンビ



ゾンビが消える

RT System Editorに関する設定



How to check the progress

- Check with Zoom's "Raise Hand Button"

The screenshot shows a Zoom control bar at the top with various icons: microphone (muted), video (off), signal strength, participant count (2), chat, share screen, recording, and response. A red box highlights the 'participants' button. Below the control bar are two participant windows. The left window shows 'test (自分)' with a green 'T' icon and a red 'raise hand' icon. The right window shows the same participant with a blue 'raise hand' icon. At the bottom, there are buttons for 'ミュートを解除します' (Unmute), '手を挙げる' (Raise Hand) in a red box, '会議ウィンドウにマージ' (Merge into meeting window), 'ミュートを解除します' (Unmute), '手を降ろす' (Lower Hand) in a red box, and '会議ウィンドウにマージ' (Merge into meeting window). A large blue callout box points to the 'participants' button with the text 'Display the participant's screen.' Another blue callout box points to the 'Raise Hand' button in the bottom row with the text 'Raise your hand if there is a problem'. A third blue callout box points to the 'Lower Hand' button in the bottom row with the text 'If it is resolved, lower your hand'.

Display the participant's screen.

Display the participant's screen.

Raise your hand if there is a problem

If it is resolved, lower your hand

RIA

ミュート解除します 手を挙げる 会議ウィンドウにマージ ミュート解除します 手を降ろす 会議ウィンドウにマージ