SEGMENTS

i = 0, joint\_id = 3, name = Hand, parent\_joint\_id: 2

i = 1, joint\_id = 4, name = HandThumb1, parent\_joint\_id: 3

i = 2, joint\_id = 5, name = HandThumb2, parent\_joint\_id: 4

i = 3, joint\_id = 6, name = HandThumb3, parent\_joint\_id: 5

i = 4, joint\_id = 8, name = HandPinky1, parent\_joint\_id: 3

i = 5, joint\_id = 9, name = HandPinky2, parent\_joint\_id: 8

i = 6, joint\_id = 10, name = HandPinky3, parent\_joint\_id: 9

i = 7, joint\_id = 12, name = HandRing1, parent\_joint\_id: 3

i = 8, joint\_id = 13, name = HandRing2, parent\_joint\_id: 12

i = 9, joint\_id = 14, name = HandRing3, parent\_joint\_id: 13

i = 10, joint\_id = 16, name = HandMiddle1, parent\_joint\_id: 3

i = 11, joint\_id = 17, name = HandMiddle2, parent\_joint\_id: 16

i = 12, joint\_id = 18, name = HandMiddle3, parent\_joint\_id: 17

i = 13, joint\_id = 20, name = HandIndex1, parent\_joint\_id: 3

i = 14, joint\_id = 21, name = HandIndex2, parent\_joint\_id: 20

i = 15, joint\_id = 22, name = HandIndex3, parent\_joint\_id: 21

i = 16, joint\_id = 24, name = Wrist, parent\_joint\_id: 3

JOINTS

i = 0, name = root

i = 1, name = pose

i = 2, name = scale

i = 3, name = Hand

i = 4, name = HandThumb1

i = 5, name = HandThumb2

i = 6, name = HandThumb3

i = 7, name = HandThumb4

i = 8, name = HandPinky1

i = 9, name = HandPinky2

i = 10, name = HandPinky3

i = 11, name = HandPinky4

i = 12, name = HandRing1

i = 13, name = HandRing2

i = 14, name = HandRing3

i = 15, name = HandRing4

i = 16, name = HandMiddle1

i = 17, name = HandMiddle2

i = 18, name = HandMiddle3

i = 19, name = HandMiddle4

i = 20, name = HandIndex1

i = 21, name = HandIndex2

i = 22, name = HandIndex3

i = 23, name = HandIndex4

i = 24, name = Wrist

DOFS

i = 0, joint\_name = pose

i = 1, joint\_name = pose

i = 2, joint\_name = pose

i = 3, joint\_name = pose

i = 4, joint\_name = pose

i = 5, joint\_name = pose

i = 7, joint\_name = Wrist

i = 8, joint\_name = Wrist

i = 9, joint\_name = HandThumb1

i = 10, joint\_name = HandThumb1

i = 11, joint\_name = HandThumb2

i = 12, joint\_name = HandThumb3

i = 13, joint\_name = HandIndex1

i = 14, joint\_name = HandIndex1

i = 15, joint\_name = HandIndex2

i = 16, joint\_name = HandIndex3

i = 17, joint\_name = HandMiddle1

i = 18, joint\_name = HandMiddle1

i = 19, joint\_name = HandMiddle2

i = 20, joint\_name = HandMiddle3

i = 21, joint\_name = HandRing1

i = 22, joint\_name = HandRing1

i = 23, joint\_name = HandRing2

i = 24, joint\_name = HandRing3

i = 25, joint\_name = HandPinky1

i = 26, joint\_name = HandPinky1

i = 27, joint\_name = HandPinky2

i = 28, joint\_name = HandPinky3

7

min:

max:

axis: 0 0 1

phalange\_id: 16, Wrist

8

min:

max:

axis: 1 0 0

phalange\_id: 16, Wrist

9

min: -0.3

max: 0.3

axis: 0 0 1

phalange\_id: 1, HandThumb1

10

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 1, HandThumb1

11

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 2, HandThumb2

12

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 3, HandThumb3

13

min: -0.5

max: 0.4

axis: 0 0 1

phalange\_id: 13, HandIndex1

14

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 13, HandIndex1

15

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 14, HandIndex2

16

min: -1.5

max: 0.1

axis: 1 0 0

type: 0

phalange\_id: 15, HandIndex3

17

min: -0.3

max: 0.3

axis: 0 0 1

phalange\_id: 10, HandMiddle1

18

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 10, HandMiddle1

19

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 11, HandMiddle2

20

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 12, HandMiddle3

21

min: -0.3

max: 0.3

axis: 0 0 1

phalange\_id: 7, HandRing1

22

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 7, HandRing1

23

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 8, HandRing2

24

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 9, HandRing3

25

min: -0.5

max: 0.3

axis: 0 0 1

phalange\_id: 4, HandPinky1

26

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 4, HandPinky1

27

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 5, HandPinky2

28

min: -1.5

max: 0.1

axis: 1 0 0

phalange\_id: 6, HandPinky3

cout << endl << "SEGMENTS" << endl;

std::vector<Segment> segments = cylinders->getSegments();

for (int i = 0; i < cylinders->getSegments().size(); i++) {

cout << endl << "i = " << i;

cout << ", joint\_id = " << skeleton->getID(segments[i].joint->getName());

cout << ", name = " << segments[i].joint->getName();

cout << ", parent\_joint\_id: " << skeleton->getID(segments[i].joint->getParent()->getName());

}

cout << endl << "JOINTS" << endl;

vector<Joint \*> &joints = skeleton->getJoints\_();

for (int i = 0; i < joints.size(); i++) {

cout << "i = " << i << ", name = " << joints[i]->getName() << endl;

}

cout << endl << "DOFS" << endl;

Mapping mapping = skeleton->getMapping();

for (int i = 0; i < mapping.jointInfos.size(); i++) {

JointInfo& jinfo = mapping.jointInfos[i];

Joint\* joint = skeleton->getJoint(jinfo.joint);

if (joint != NULL) {

cout << "i = " << i << ", joint\_name = " << joint->getName() << endl;

}

}