

## Robot Control Interface - Feature #1714

### Provide rci::wrench converter in rst-converters

01/06/2014 08:20 AM - C. Emmerich

<b>Status:</b>	Resolved	<b>Start date:</b>	01/06/2014
<b>Priority:</b>	High	<b>Due date:</b>	
<b>Assignee:</b>		<b>% Done:</b>	100%
<b>Category:</b>	Software	<b>Estimated time:</b>	0.00 hour
<b>Target version:</b>	rsb-0.11		
<b>Description</b>			
Please provide a rst-converter for rci::Wrench type			
<b>Related issues:</b>			
Related to Robot Control Interface - Feature # 1715: Provide better interface...		<b>Resolved</b>	<b>01/06/2014</b>

#### History

##### #1 - 01/06/2014 09:53 AM - Anonymous

- Tracker changed from Enhancement to Feature
- Category set to Software
- Assignee deleted (Anonymous)
- Target version set to rsb-0.11

Should be easy to add by yourself to the rst-converters repository (git: [/projects/rst/repository/rst-converters](https://github.com/roboticstools/rst-converters)).

You could use the PoseConverter as sample, as it basically does the same.

##### #2 - 01/06/2014 10:03 AM - C. Emmerich

I don't think so. Since a rci::Wrench is stored as quaternions and a rst.wrench as 3-dim torque, I do not know how to convert between them (on a technical as well as a conceptual level). Maybe you should have a look at #1043, it might be related to this issue.

##### #3 - 01/20/2014 09:09 AM - C. Emmerich

- Status changed from New to Resolved
- % Done changed from 0 to 100

Since the automatic issue-closing mechanism did not work here, I close this issue manually...

Converter is implemented [here](#)