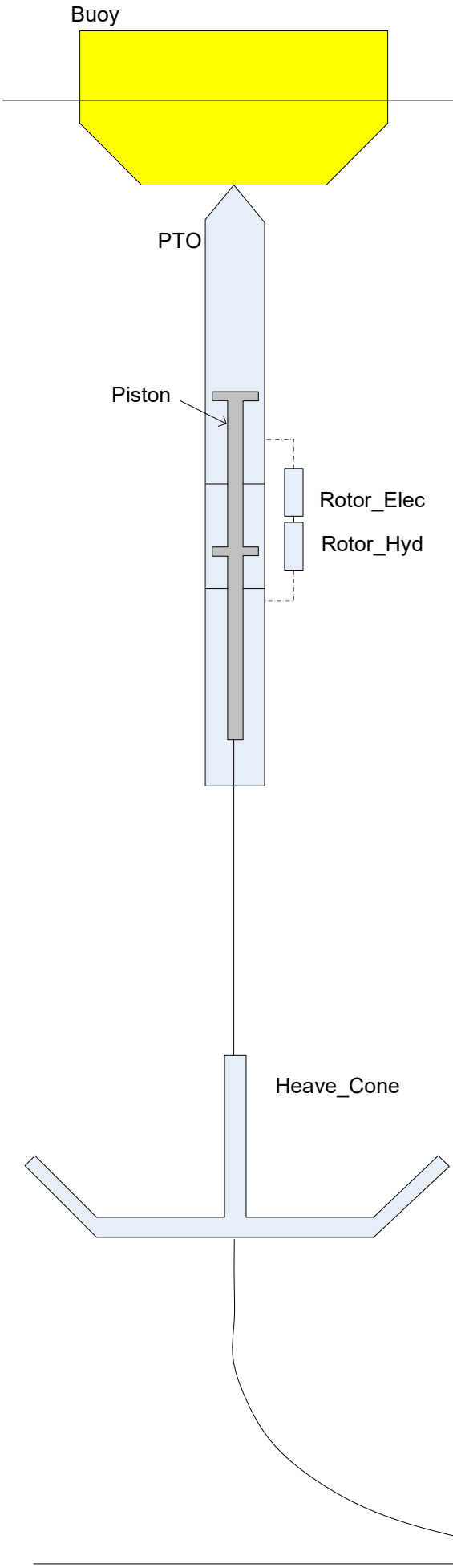


Rigid Bodies

Buoy: 6 DOF relative to world, subject to:
- Gravity
- Buoyancy (Free-Surface)
- Wave-Exciting Forces
- Wave-Diffraction Forces
- Wave-Radiation Forces
- Drag Forces

PTO: 2 DOF relative to Buoy, subject to:
- Gravity
- Buoyancy (constant)
- Pneumatic Spring Force
- Hydraulic Force
- Friction from Piston
- Force from tether

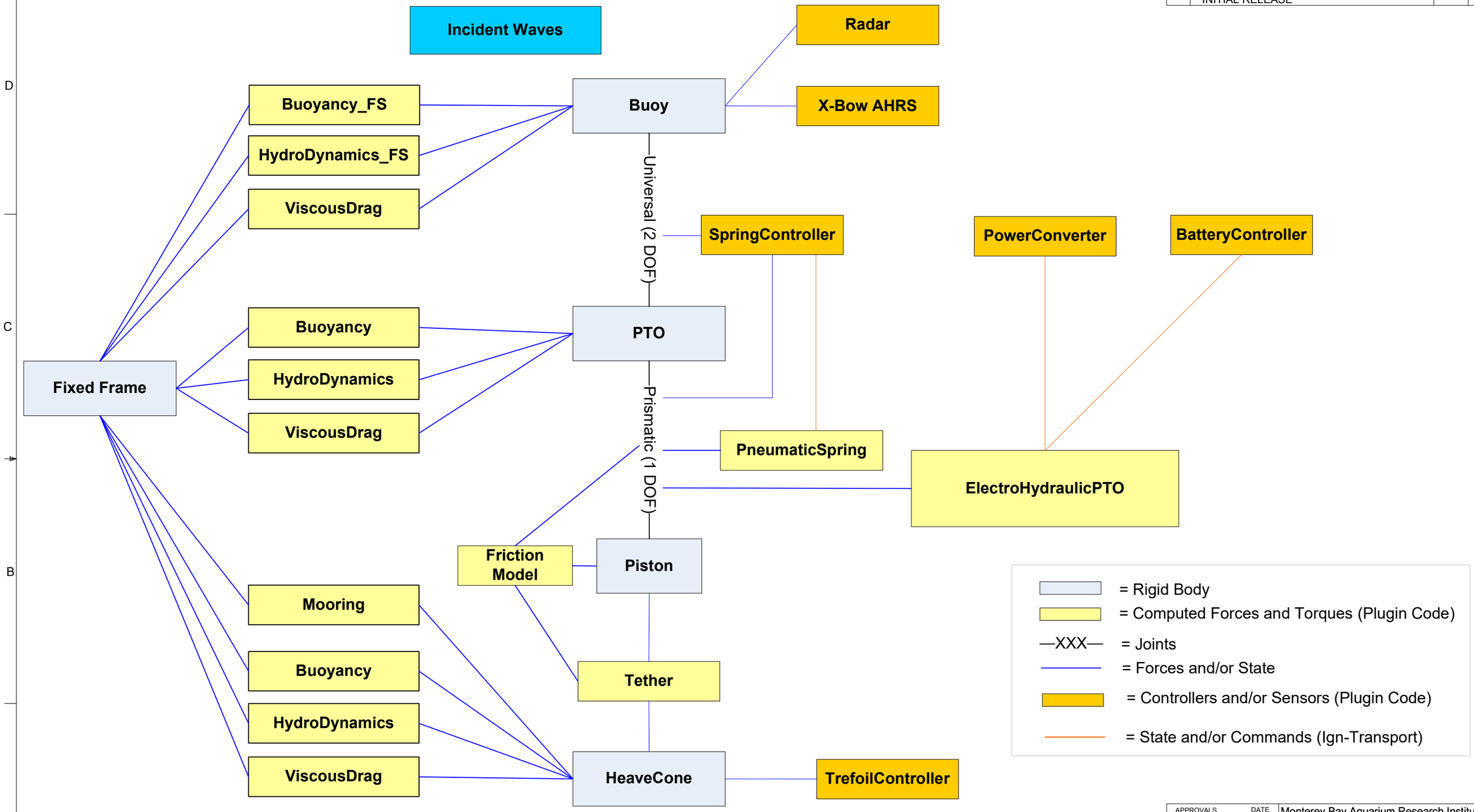
Piston: 1 DOF (linear) relative to PTO, subject to:
- Limits of travel constraint
- Gravity
- Pneumatic Spring Force
- Hydraulic Force
- Friction from PTO
- Force from tether

Rotor_Hyd: 1 DOF (rotational) relative to PTO, subject to:
- Hydraulic torque

Rotor_Elec: 1 DOF (rotational) relative to PTO, subject to:
- Electrical torque

Heave_Cone: 6DOF relative to world, subject to:
- Gravity
- Buoyancy (constant)
- Hydrodynamics
- Drag Forces
- Force from Tether
- Force from Mooring

REVISIONS			
REV.	DESCRIPTION	DATE	APPROVED
	INITIAL RELEASE		



APPROVALS	DATE
DRAWN NAME	9/27/00
ENGINEER NAME	9/27/00
CHECKED	
PROJECT NO. XXX	
PROJECT ZZZZZZZZ	

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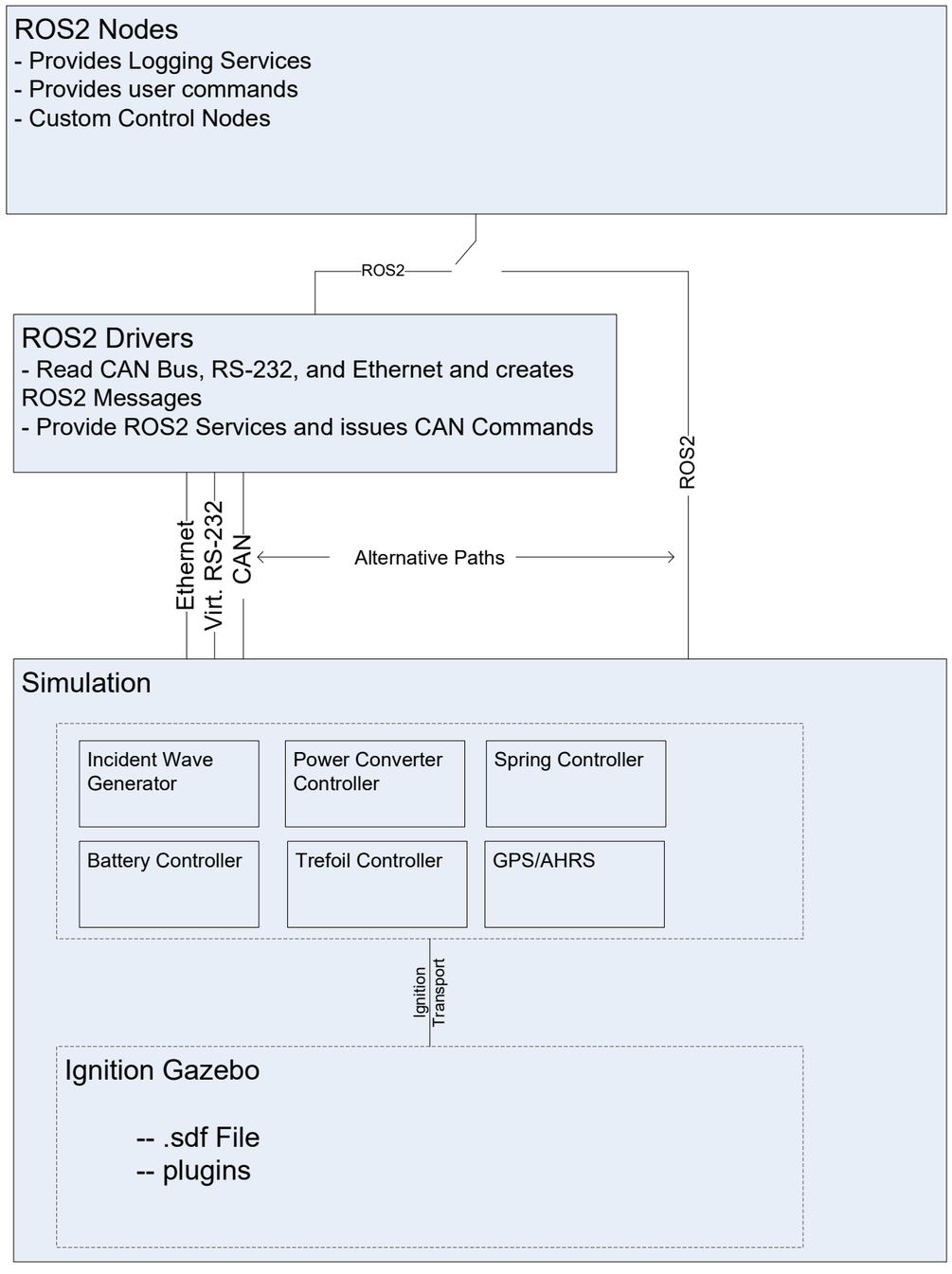
SIZE	DWG. NO.	REV.
B	100XXXDWG	

FILE: SHEET 1 OF 1


ROS2 Nodes
- Provides Logging Services
- Provides user commands
- Custom Control Nodes
ROS2
ROS2 Drivers
- Read CAN Bus, RS-232, and Ethernet and creates ROS2 Messages
- Provide ROS2 Services and issues CAN Commands
Ethernet
Virt. RS-232
CAN
Alternative Paths
ROS2
Simulation
Incident Wave Generator
Power Converter Controller
Spring Controller
Battery Controller
Trefoil Controller
GPS/AHRS
Ignition Transport
Ignition Gazebo
-- .sdf File
-- plugins