
Libralis Library Quick Reference

This section illustrate how to get started using Libralis with Haptik Library.

- Add the files libralis.h and libralis.cpp to your existing C++ project.
- In your **Project properties**, add the following path
[ProgramFolder] \ Siena Robotics and System Lab\Libralis Library\Include
to **Additional Include Directories**, and the following path
[ProgramFolder] \ Siena Robotics and System Lab\Libralis Library\Lib
to **Additional Library Directories**.
- Include the header libralis.h to C++ file in which you have implemented the haptic servo-loop.
- In libralis.h, you have to define the correct path and filename to access the gravity data file, with NO file extension.
- If you are using Visual Studio.NET, please be sure to set the Runtime Library property /MDd.

Please refer to the **sampleLibralis** project, in your Libralis Library folder.

If you desire to replace Haptik with a different API, the file libralis.h should be edited as shown in the following example:

```
#include <windows.h>

#include "LibralisFunctions.h"

#include <myHapticAPI.h>

using namespace my_Haptic_API;

#define GRAVITY_COMPENSATION_FILE __TEXT("./path/filename")

bool InitLibralis();

my_3D_vector_type Compensate(my_3D_vector_type position);
```

Consequently, also the implementation in file libralis.cpp should be edited accordingly.