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# This is a sample description file showing how to connect
# a model with a Phantom haptic server
# CWC, April 2007
#
# This features a single tool, and the connection to the sensor.
dilatator0.smf
    dynamics: 0
    behavior: probing
    scale_vector: 1.0 1.0 -3.0
    ambient: .4 .4 .8 1.
    diffuse: .4 .4 .8 1.
    sensoroffset: 0 0 30      # 14
    tipnode: 0
    collisionfaces: 288
    collisionextent: 1 # external

internal
    collision: 1
    collisionalgorithm: BoundingSphere
    createsensor: haptic_v1 177.13.37.42#9999 2.0 0.05 -180 0 20
    translation: 0.0, 0.0, 0.0
    attach: 0 dilatator0
```