**User Guide**

To prepare your environment you must :

* Print an ar-tag following instructions from here <http://wiki.ros.org/ar_track_alvar>
* Measure the size of one of the side of the ar-tag
* Stick the ar-tag on the object you want to manipulate
* Put the object on the working area with the ar-tag fully visible to the baxter
* Avoid as much as possible any sun illumination and if possible have a uniform light

To Run the program you must :

* Launch a terminal
* Go to your Ros Project Baxter Pick and Place directory : “cd [..]/ros\_ws”
* Run baxter.sh : “./baxter.sh”
* Launch the program : “roslaunch pick\_and\_place LearningScenarioARStereo.launch” to learn to the program the desired situation relative to the ar-tag at the end of the visual servoing (follow the instructions in the terminal)
* Launch the program : “roslaunch pick\_and\_place PickAndPlaceScenarioARStereo.launch” to do the procedure of pick and place of the object (follow the instructions in the terminal)