

## 安装

```
sudo apt-get install \  
ros-kinetic-ur-gazebo \  
ros-kinetic-ur3-moveit-config \  
ros-kinetic-ur-kinematics
```

## 启动

```
roslaunch ur_gazebo ur3.launch  
roslaunch ur3_moveit_config ur3_moveit_planning_execution.launch sim:=true  
roslaunch ur3_moveit_config moveit_rviz.launch config:=true
```

## 移动

motionplanning- plan- start/ goal state- plan and execute