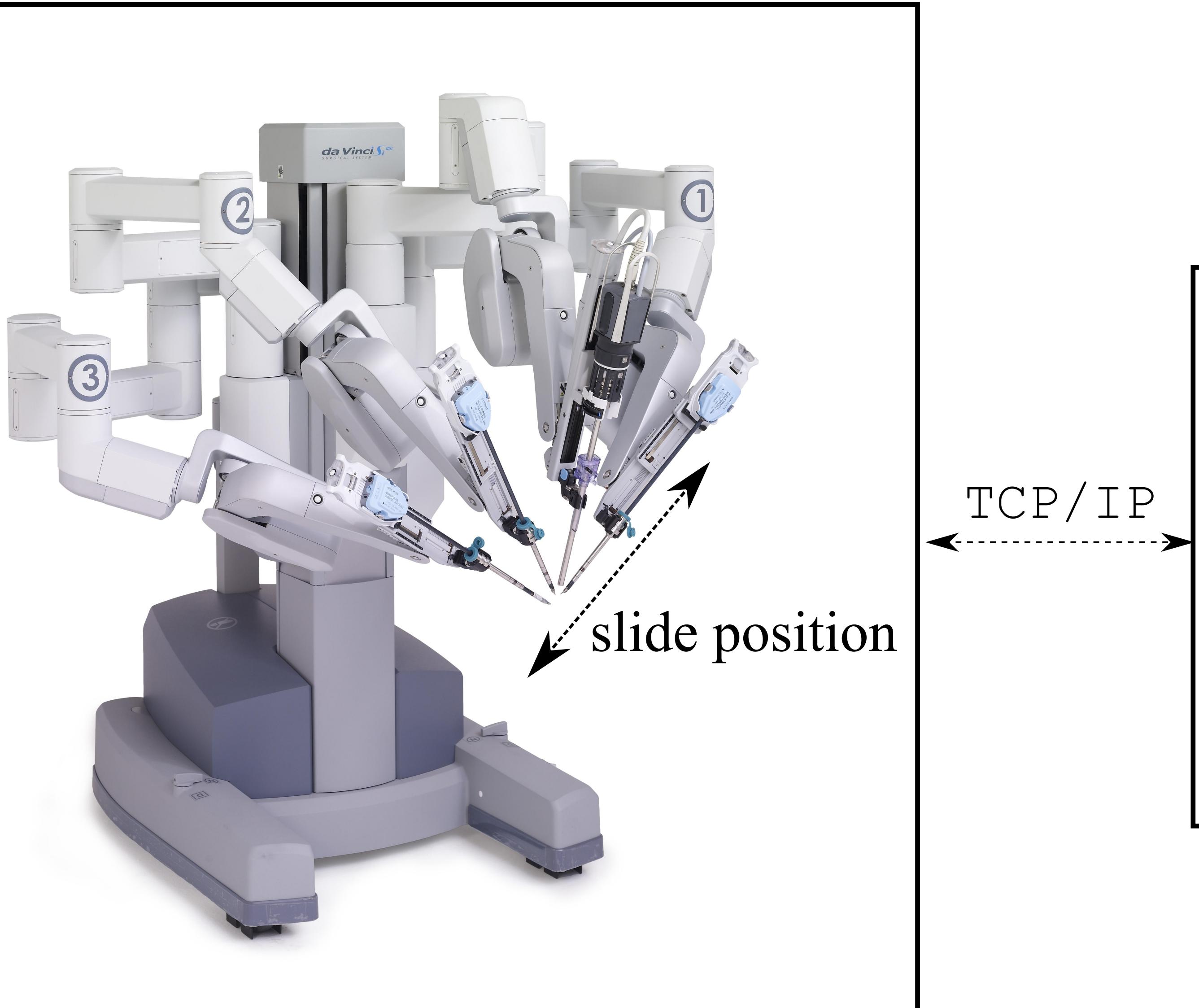


# Da Vinci Robot



TCP/IP



Laptop

```
(1) $ roscore  
.  
.  
.  
(2) $ roslaunch davinci_driver davinci_driver.launch  
....  
.  
.  
.  
.  
.  
(3) $ roslaunch davinci_move_group move_group.launch  
....  
.  
.  
.  
.  
.  
(4) $ rosrun davinci_move_group moveGroupInterfaceExecute  
....  
.  
.  
.  
.  
.  
(5) $ rostopic echo joint_states/position[6]  
...  
....
```