

Start

Self-Collisions

Virtual Joints

Planning Groups

Robot Poses

End Effectors

Passive Joints

Configuration Files

Movelt Setup Assistant

Welcome to the Movelt Setup Assistant! These tools will assist you in creating a Movelt configuration package that is required to run Movelt. This includes generating a Semantic Robot Description Format (SRDF) file, kinematics configuration file and OMPL planning configuration file. It also involves creating launch files for move groups, OMPL planner, planning contexts and the planning warehouse.



Choose mode:

All settings for Movelt are stored in a Movelt configuration package. Here you have the option to create a new configuration package, or load an existing one. Note: any changes to a Movelt configuration package outside this setup assistant will likely be overwritten by this tool.

Create New Movelt
Configuration Package

Edit Existing Movelt
Configuration Package

Load Movelt Configuration Package Path

Specify the package name or path of an existing Movelt configuration package to be edited for your robot. Example package name: *pr2_moveit_config*

/afs/ies.auc.dk/user/ckly10/Private/davinci_ws/src/davinci_moveit_config

Browse



Load Files