## Setup

Kinova Pick Place

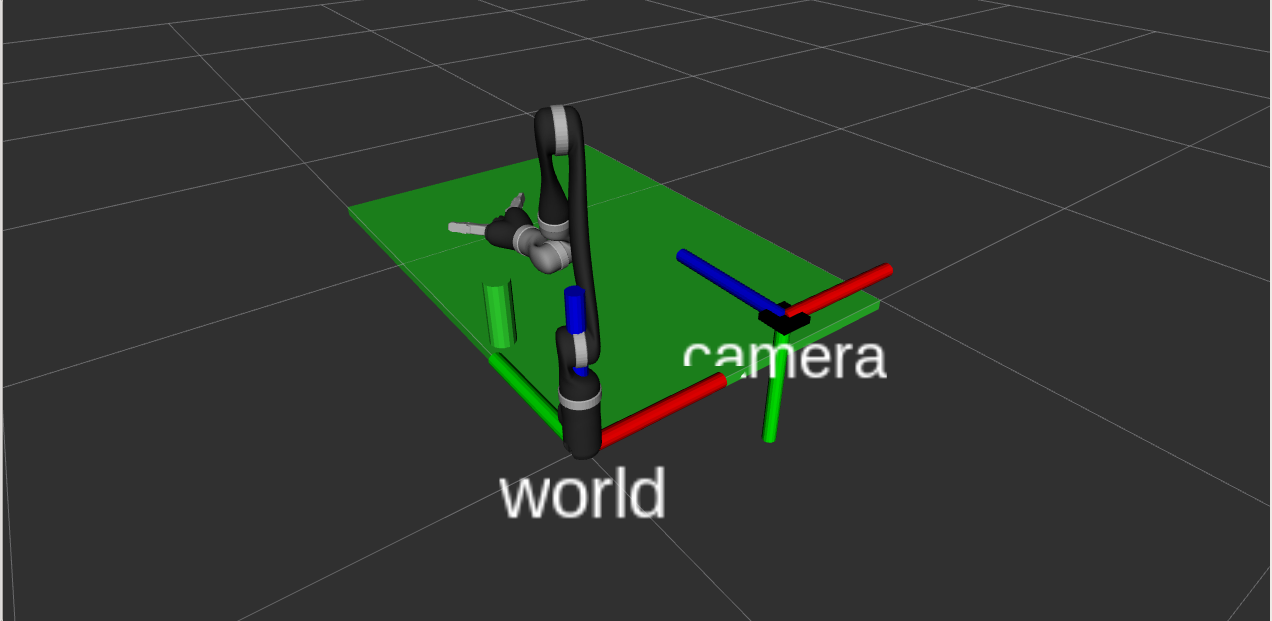
\* move kinova\_pick\_place directory into : /catkin\_ws/src/kinova-ros/kinova\_moveit/

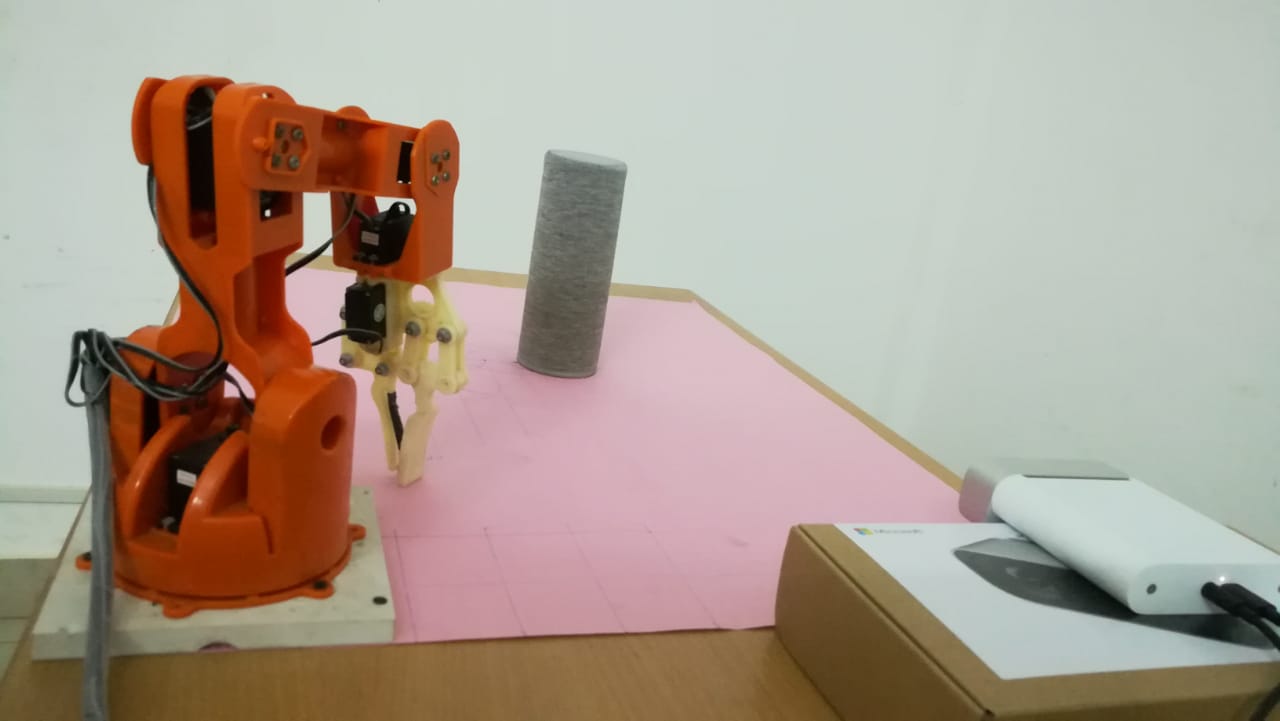
PCL Package

\* Replace pcl\_pkgs

\* Compile : catkin\_make

Camera Setup :





**Camera coordinates**: +x points right, +y points down and +z points forward.

**Assumed robot coordinates**: +x points right, +y points forward, and +z points up

STEPS

1.Launch Driver

roslaunch kinova\_bringup kinova\_robot.launch kinova\_robotType:=j2s6s300

2.Moveit

roslaunch j2s6s300\_moveit\_config j2s6s300\_robot\_demo.launch

3.Launch Kinect Driver

roslaunch azure\_kinect\_ros\_driver driver.launch depth\_mode:=NFOV\_UNBINNED color\_enabled:=false rgb\_point\_cloud:=false

4. Start PCL

rosrun pcl\_pkgs cylinder input:=/kinect/points2 x y z

Note: change camera topic accordingly and specify camera positions.

5. Run Pick Place node

rosrun kinova\_pick\_place jaco\_pick\_place

## Fix in gripper close action:

* Replace catkin\_ws/src/kinova-ros/kinova\_moveit/robot\_configs/j2s6s300\_moveit\_config with Required Folders v0.3/j2s6s300\_moveit\_config
* Replace catkin\_ws/src/kinova-ros/kinova\_moveit/kinova\_pick\_place with Required Folders v0.3/kinova\_pick\_place
* Compile