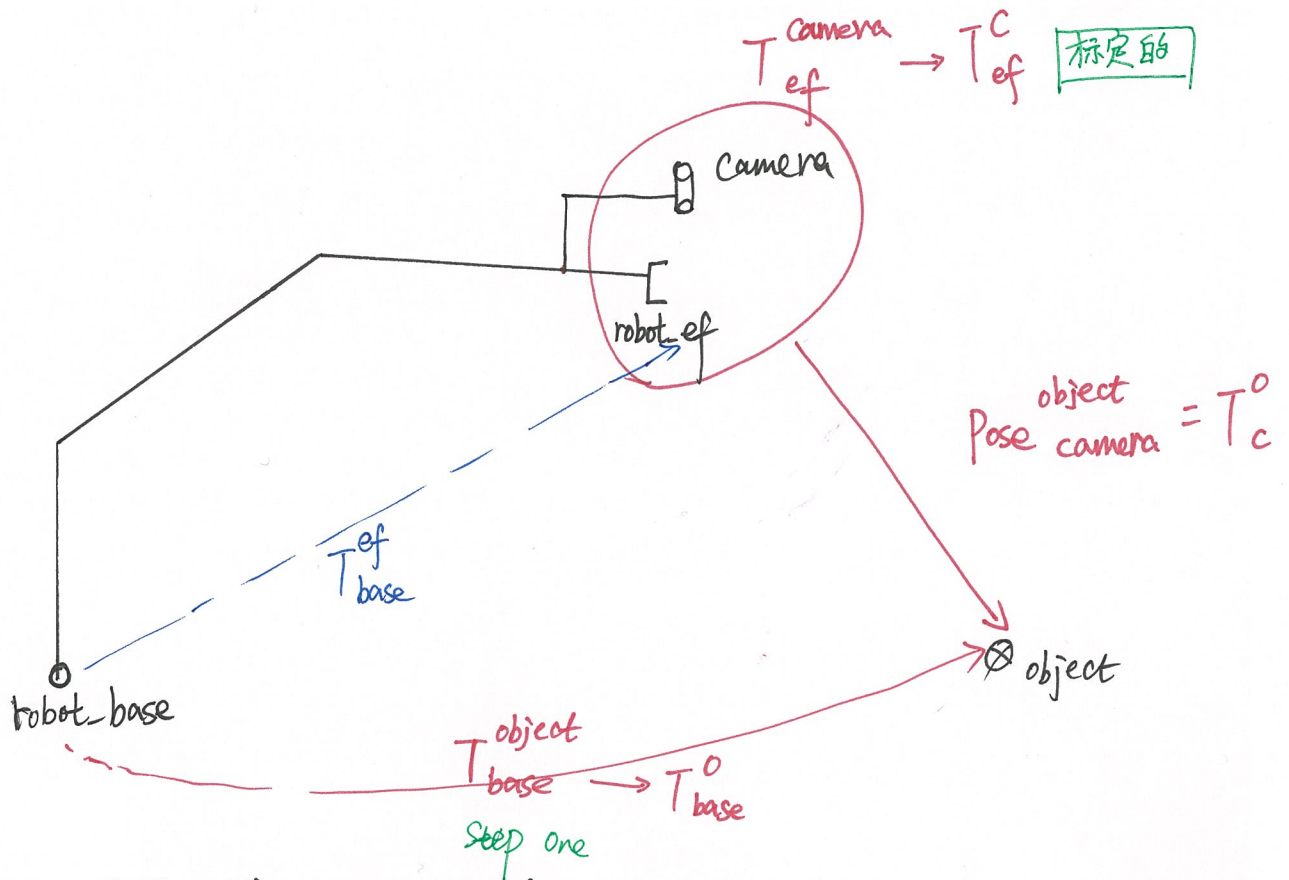


Calibrate.



Current Configuration: can get from tf tree

①. $T_{base}^o = T_{base}^{ef} \cdot T_{ef}^c \cdot T_c^o$
 假设不动. ~~~~~ current pose wrt camera

②. Get the desired end-effector Pose wrt robot_base.

$$T_{base}^{ef} = T_{base}^o \cdot \overset{\text{desired}}{(T_c^o)^T} \cdot (T_{ef}^c)^T$$

①
desired pose
calibration

③ Set T_{base}^{ef} to Robot iina