Eye Hand Calibration

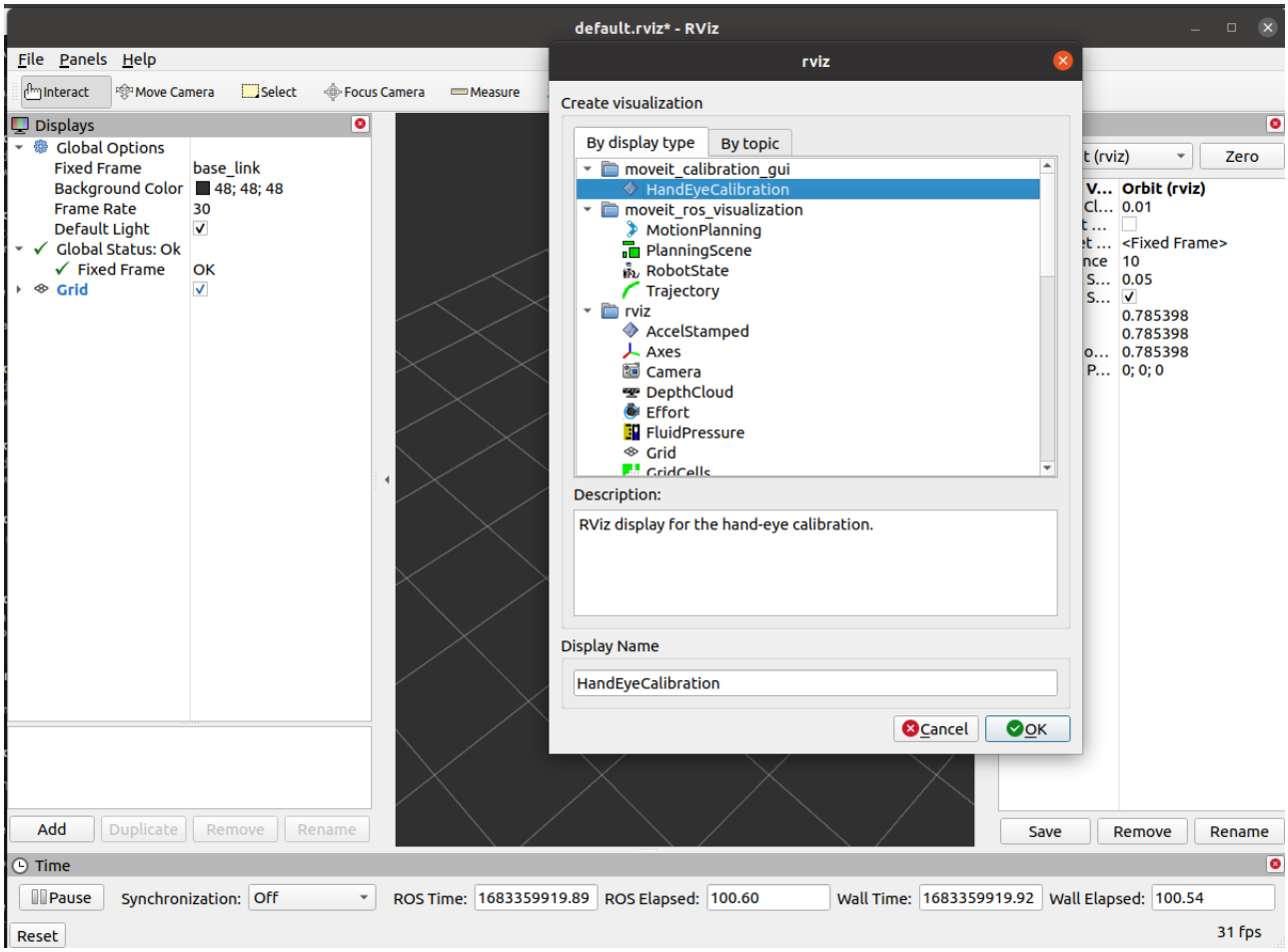
1. Download ROS Packages

```
cd ~/catkin_ws/src # your workspace
git clone https://github.com/ros-planning/moveit_calibration.git
git clone https://github.com/PickNikRobotics/rviz_visual_tools.git
sudo apt update
sudo apt upgrade
sudo apt install ros-noetic-graph-msgs
sudo apt install ros-noetic-moveit-visual-tools
sudo apt install ros-noetic-geometric-shapes
sudo apt install ros-noetic-handeye
cd ~/catkin_ws
rm -rf build/ devel/
catkin_make
```

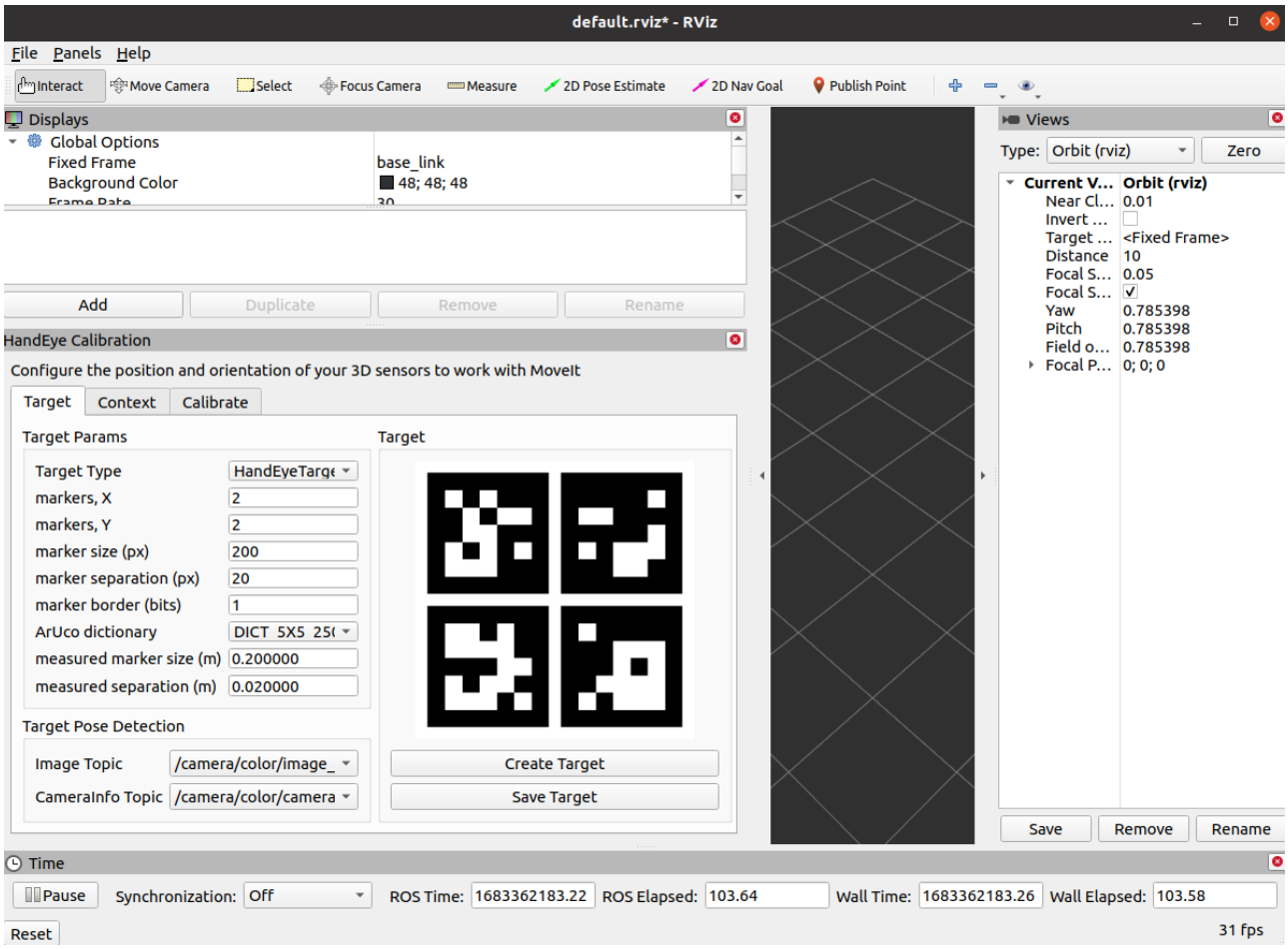
2. Launch Kinova Driver and Camera Driver

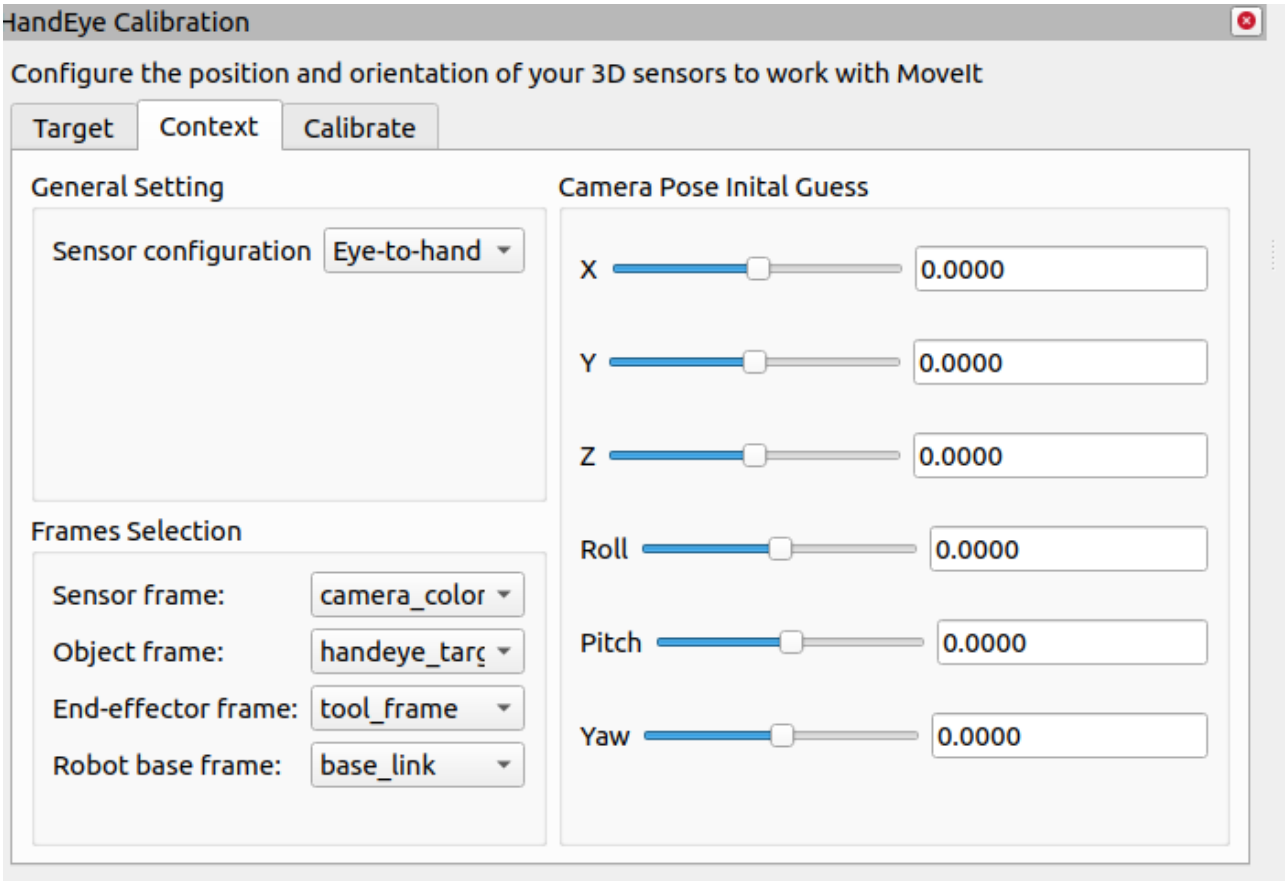
```
roslaunch kortex_driver kortex_driver
roslaunch realsense2_camera rs_aligned_depth.launch
```

3. Add hand eye calibration in rivz



4. Set parameters





5. Take Samples and save camera pose