

# Eye Hand Calibration

---

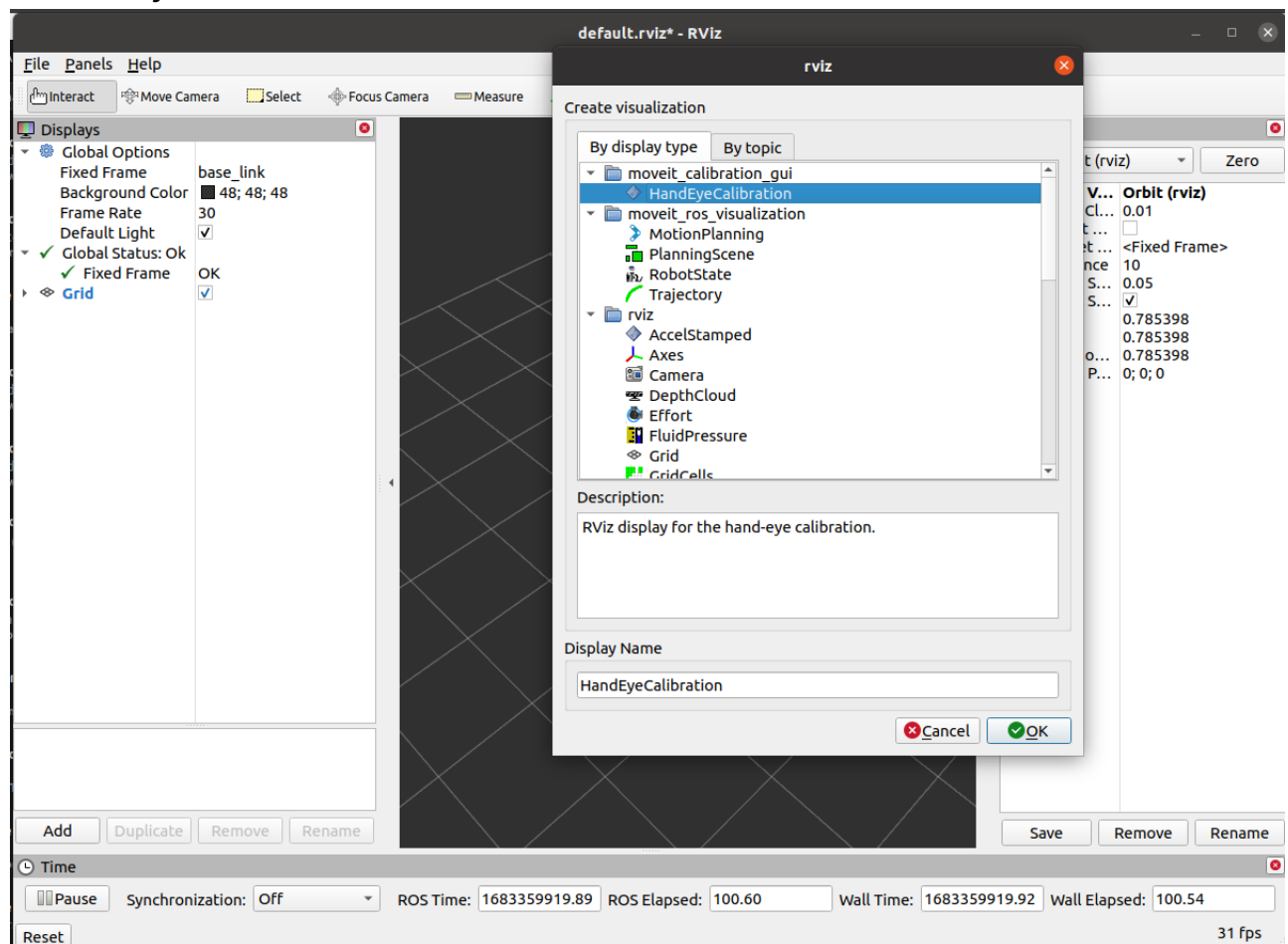
## 1. Download ROS Packages

```
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
```

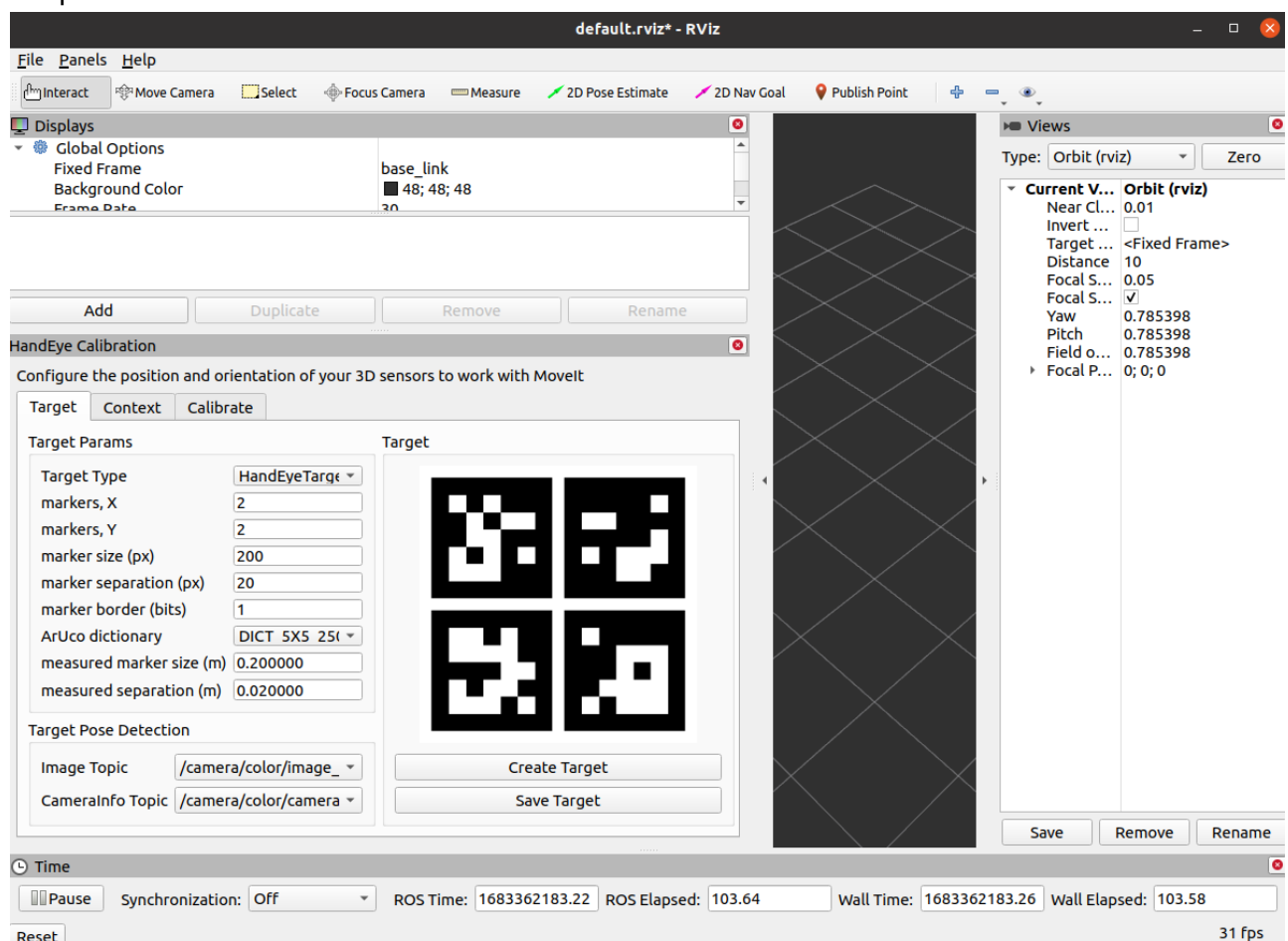
## 2. Launch Kinova Driver and Camera Driver

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

### 3. Add hand eye calibration in rivz



### 4. Set parameters



HandEye Calibration

Configure the position and orientation of your 3D sensors to work with MoveIt

Target Context Calibrate

General Setting

Sensor configuration Eye-to-hand

Frames Selection

Sensor frame: camera\_color

Object frame: handeye\_target

End-effector frame: tool\_frame

Robot base frame: base\_link

Camera Pose Initial Guess

X 0.0000

Y 0.0000

Z 0.0000

Roll 0.0000

Pitch 0.0000

Yaw 0.0000

5. Take Samples and save camera pose