#### README #### Second assignment ####

* #1 Open MATLAB
* #2 Open “startupExample.m” and run it in the editor
* #3 Open “manipTrajCartesian.m” and run in the editor
* #4 Open “createWayPointData.m” to view the coordinates in the plane

#### README #### Final demo file ####

Some of the command lines which need to follow to run the demo:

* Open a terminal and write “sudo cp catkin\_ws/src/kinova-ros/kinova\_driver/udev/10-kinova-arm.rules /etc/udev/rules.d/ “
* Open a new terminal and write these lines and run :
  + roslaunch kinova\_bringup kinova\_robot.launch kinova\_robotType:=j2n6s300
  + rosservice call /j2n6s300\_driver/in/home\_arm
  + rosrun kinova\_demo pose\_action\_client.py -v j2n6s300 mdeg -- 0.51 0 0 0 0 20
  + rosrun kinova\_demo fingers\_action\_client.py j2n6s300 percent -- 100 100 100

We manually write the given coordinates from the vision control and arm follows it.