

# SKUBA 2015 Object Recognition Report

object.description.1

```
desdenona@desdenona:~/skuba_athome/src/manipulator$ cat controllers.yaml joint_limits.yaml kinematics.yaml luma1_nell.srdf ompl_planning.yaml sensors_rgbd.yaml
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ vi controllers.yaml
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ ls
fake_controllers.yaml joint_limits.yaml kinematics.yaml luma1_nell.srdf ompl_planning.yaml sensors_rgbd.yaml
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ vi joint_limits.yaml
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ vi kinematics.yaml
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ vi luma1_nell.srdf
desdenona@desdenona:~/skuba_athome/src/manipulator/configs$ roscd manipulator/
desdenona@desdenona:~/skuba_athome/src/manipulators$ vi nodes/
backup_manipulator.py inversekinematic.py manipulator_old.py pick_place_tutorial.cpp
inversekinematic.py manipulator_node.py manipulator_open.py
desdenona@desdenona:~/skuba_athome/src/manipulators$ vi nodes/pick_place_tutorial.cpp
desdenona@desdenona:~/skuba_athome/src/manipulators$ cd -
/home/desdenona/skuba_athome/src/manipulator
desdenona@desdenona:~/skuba_athome/src/manipulator$ rosrunc manipulator pick_place_tutorial
[ INFO ] [1433727343.336518847]: Loading robot model 'luma1_nell'...
[ INFO ] [1433727343.965829284]: Loading robot model 'luma1_nell'...
[ WARN ] [1433727344.317501499]: The root link base_link has an inertia specified in the URDF, but KDL does not support a root link with an inertia. As a workaround, you can add an extra dummy link to your URDF.
[ INFO ] [1433727344.324539595]: Loading robot model 'luma1_nell'...
[ WARN ] [1433727344.679358768]: The root link base_link has an inertia specified in the URDF, but KDL does not support a root link with an inertia. As a workaround, you can add an extra dummy link to your URDF.
[ INFO ] [1433727344.686561072]: Loading robot model 'luma1_nell'...
[ INFO ] [1433727345.052123508]: Group 'right_gripper' is not a chain
[ ERROR ] [1433727345.05213618]: Kinematics solver of type 'kdl_kinematics_plugin/KDLKinematicsPlugin' could not be initialized for group 'right_gripper'
[ ERROR ] [1433727345.052272886]: Kinematics solver could not be instantiated for joint group right_gripper.
[ INFO ] [1433727345.058124784]: Loading robot model 'luma1_nell'...
[ ERROR ] [1433727345.440325178]: Group 'left_gripper' is not a chain
[ ERROR ] [1433727345.440325233]: Kinematics solver of type 'kdl_kinematics_plugin/KDLKinematicsPlugin' could not be initialized for group 'left_gripper'
[ INFO ] [1433727346.318537994]: Ready to take MoveGroup commands for group right_arm.
[ INFO ] [1433727346.559994535]: Ready to take MoveGroup commands for group left_arm.
[ INFO ] [1433727347.214065237]: ABORTED: No motion plan found. No execution attempted.
[ WARN ] [1433727348.506087764]: Fail: ABORTED: No motion plan found. No execution attempted.
[ WARN ] [1433727349.268087300]: Fail: ABORTED: Must specify group in motion plan request
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desdenona@desdenona:~/skuba_athome/src/manipulators$ cd -
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