Note:

1. This project is from the course, ROS Manipulation in 5 Days on Robot Ignite Academy

: https://www.robotigniteacademy.com/en/course/ros-manipulation-in-5-days/details/

2. Any contents of the project belong to Robot Ignite Academy except for the sample solution written by Samwoo Seong. I.e. I don't own any of the project contents

3. Any work throughout the project is for learning purpose

4. The solution written by Samwoo Seong shouldn't be used to pass the project on this course

<Requirements>

-One of ROS 1 distributions

-Gazebo

-RB15 Running on Gazebo Simulation

<How to Run my program on Robot Ignite Academy>

1. Type this in one of terminals

roslaunch rb1_moveit_config project_planning_execution.launch

```
user:~$ roslaunch rb1_moveit_config project_planning_execution.launch
```

2. Spawn Table

rosrun gazebo_ros spawn_model -file /home/user/catkin_ws/src/table.urdf -urdf -x 1 -model my_object

```
user:~$ rosrun gazebo_ros spawn_model -file /home/user/catkin_ws/src/table.urdf -urdf -x 1 -model my_object
```

3. Spawn Cube

rosrun gazebo_ros spawn_model -database demo_cube -gazebo -model grasp_cube -x 0.50 -y -0.04 -z 0.6

```
user:~$ rosrun gazebo_ros spawn_model -database demo_cube -gazebo -model grasp_cube -x 0.50 -y -0.04 -z 0.6
```

4. Type the following in another terminal

rosrun simple_grasping gripper_test.py

```
user:~$ rosrun simple_grasping gripper_test.py
```