ENPM661: path planning for panda using moveit

TEAM MEMBERS:

Dhanush Babu Allam (dallam)- 119390320

Sourang Sri Hari (sourang)- 119074947

VIDEO LINK:

https://drive.google.com/file/d/16PZkhumFTHUgJeDJZSV6zzRLeVCjsYNt/view?usp=share_link

Steps:-
- A workspace was created named moveit_ws, and installed moveit_tutorials and panda_moveit_config.
- The table.stl file which is a mesh was added to the pick_place_tutorial.cpp file
- An obstacle was created in pick_place_tutorial.cpp, an object was created to pick and place.
- The location for picking and placing was set,i.e. pre-pick, grasping, and post-picking position and orientation was set. Similarly, the goal loaction was set.
- The opengripper() function was modified so the gripper is larger than then object, and the closegripper() function was modified so the gripper width is same as the object for picking.

CONTRIBUTIONS:

	DHANUSH	SOURANG	TOPICS
1	X	X	INSTALLATION AND SETUP
2	X	X	IMPORTING THE

			TABLE
3	X	X	CPP FILE MODIFICATION
4	X	X	TYPING REPORT