

This source code contains various versions of C++ code where two of the important and most useful ones are used:

1. One for the socket test, that is to be performed on SocketTest3. The source code for this is present in between the comments //code for socket test (start) and // code for socket test (end)
2. Another one is for executing in the python version, where the code sends the coordinates of the Kinect camera to the Kinova Robot, and this robot uses these coordinates to perform action. This source code is present in between the comments //code for testing in python (start) and // code for testing in python (end).
3. Another important thing is, this code sends all the coordinates of the Kinect camera to the Kinova Robot (python code), but the python code only needs to perform actions based on the 10<sup>th</sup> (right shoulder angle) and 11<sup>th</sup> (left shoulder angle) element of the coordinates array sent from the C++ program to the python program. Only these two coordinates are required for making the Kinova robot to perform simple applications of pick and place.