

Movelt control the real machine

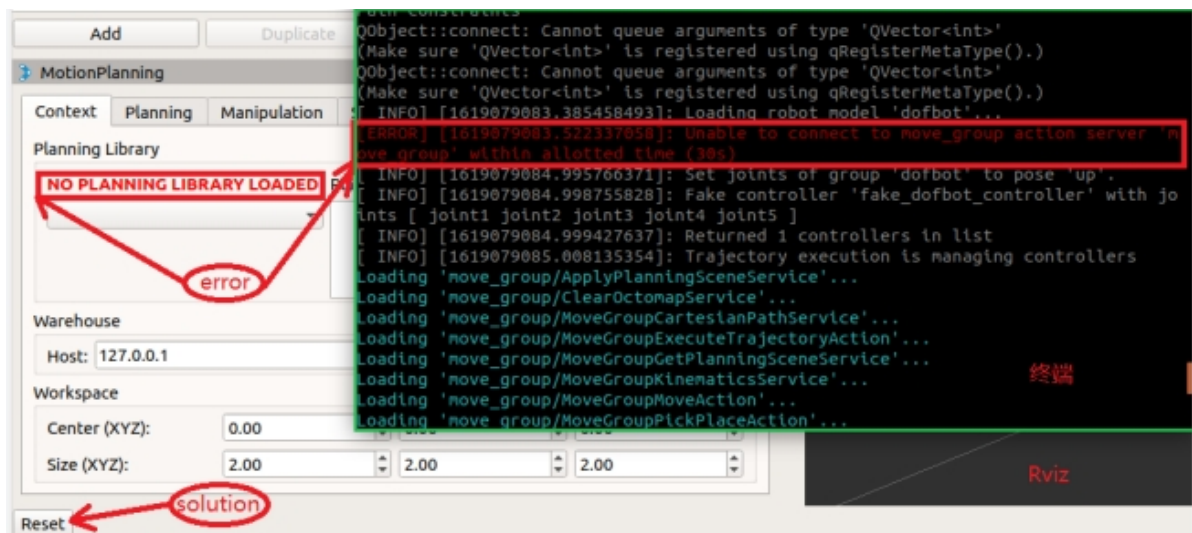
Follow the previous steps to install the virtual machine. After decompressing the system files, open the virtual machine and use it. The environment has been set up and the relevant code has been placed in the Ubuntu system, in the file path /home/dofbot/dofbot_ws/src directory.

1. Start up robotic arm

- When using the robot arm to move randomly to control a real machine, pay attention to the movement of the robot arm. Try to keep no objects next to the robot arm, because random movement will cause random walking.
- Scene Design: You can design the scene yourself and then import it.
- When movelt is run and combined with the real machine case, there are non-corresponding actions. It may be because the previous control program has not been completely closed. You can try using Ctrl+C to interrupt the program, or simply close the terminal to shut down the previous process more completely.

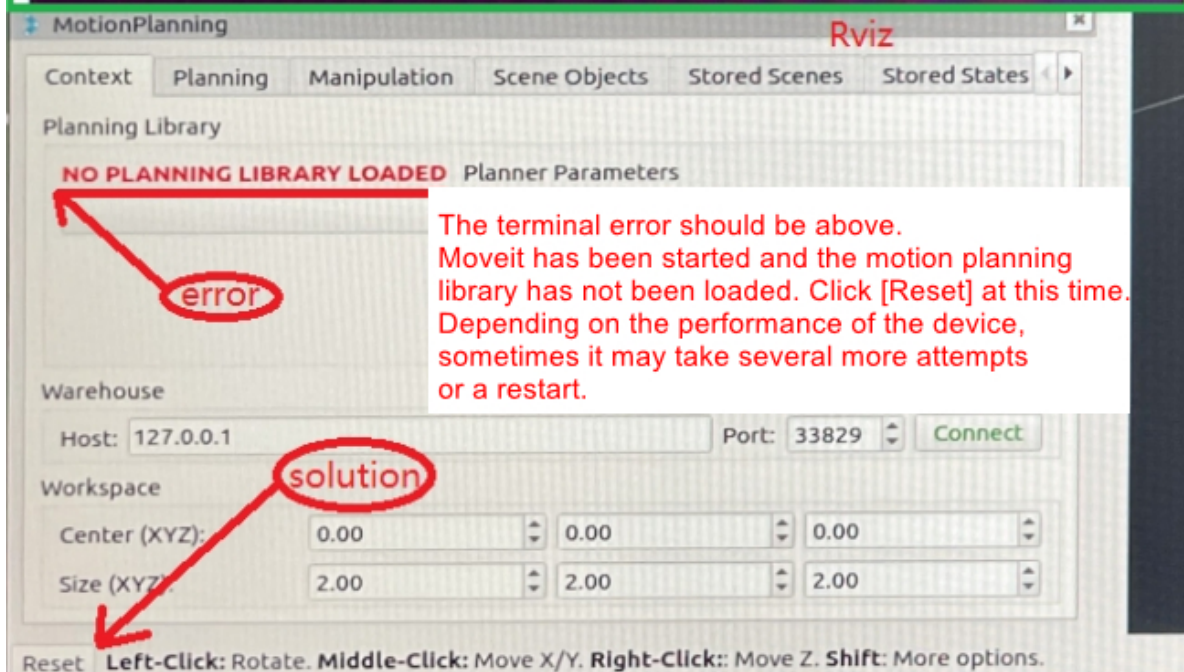
2. Start up MoveIt

The MoveIt simulation environment starts slowly, so wait patiently and observe the terminal. An error occurs as shown in the figure below. The solution is as shown in the figure. If the terminal reports an error and the motion planning library is not loaded, click [Reset] in the lower left corner and reload. At first, it is during the loading process. Don't rush to click [Reset]. If you click it before loading is complete, the system will reload and it will not start.



```
/home/jetson/dofbot_ws/src/dofbot_config/launch/demo.launch http://localhost:11311
[ INFO] [1619081389.725846519]:
*****
* MoveGroup using:
*   - ApplyPlanningSceneService
*   - ClearOctomapService
*   - CartesianPathService
*   - ExecuteTrajectoryAction
*   - GetPlanningSceneService
*   - KinematicsService
*   - MoveAction
*   - PickPlaceAction
*   - MotionPlanService
*   - QueryPlannersService
*   - StateValidationService
*****
I
[ INFO] [1619081389.726033396]: MoveGroup context using planning plugin ompl_int
erface/OMPLPlanner
[ INFO] [1619081389.726107720]: MoveGroup context initialization complete
You can start planning now!
```

终端



```
[INFO] [1619079085.126261894]: MoveGroup context using planning plugin ompl_interface/OMPLPlanner
[INFO] [1619079085.126296501]: MoveGroup context initialization complete

You can start planning now!

[INFO] [1619079144.018331969]: Stopping planning scene monitor
[WARN] [1619079144.058627471]: SEVERE WARNING!!! Attempting to unload library while objects created by this loader exist in the heap! You should delete your objects before attempting to unload the library or destroying the ClassLoader. The library will NOT be unloaded.
[INFO] [1619079144.060378130]: Loading robot model 'dofbot'...
[INFO] [1619079153.366458947]: Starting planning scene monitor
[INFO] [1619079153.368822804]: Listening to '/move_group/monitored_planning_scene'
[INFO] [1619079156.233051823]: Constructing new MoveGroup connection for group 'dofbot' in namespace ''
[INFO] [1619079157.321685434]: Ready to take commands for planning group dofbot.
[INFO] [1619079157.321798709]: Looking around: yes
[INFO] [1619079157.321866431]: Replanning: yes
```

