Movelt collision detection

1. RVIZ simulation motion of robotic arm

1.1 Start roscore

- If you are using Jetson Orin NX/Jetson Orin Nano board. You need to enter the Docker environment using the following command.

```
sh ~/start_docker.sh
roscore
```

- If you are using Jetson Nano board. You need to enter the following command directly.

```
roscore
```

1.2 Start simulation

Open a new terminal.

- If you are using Jetson Orin NX/Jetson Orin Nano board. You need to enter the Docker environment using the following command.

```
sh ~/start_docker.sh
```

- If you are using Jetson Nano board. You need to enter the following command directly.

```
roslaunch jetcobot_moveit jetcobot_moveit.launch
```

2. Drive real robotic arm

Open a new terminal.

- If you are using Jetson Orin NX/Jetson Orin Nano board. You need to enter the Docker environment using the following command.

```
sh ~/start_docker.sh
```

- If you are using Jetson Nano board. You need to enter the following command directly.

```
rosrun jetcobot_moveit sync_plan.py
```

Note: After the program driving the real machine is running, the robotic arm will follow the movement of the simulated robot.

Please be careful not to place other objects around to avoid being hit by the robotic arm.

4. Run program

Open a new terminal.

- If you are using Jetson Orin NX/Jetson Orin Nano board. You need to enter the Docker environment using the following command.

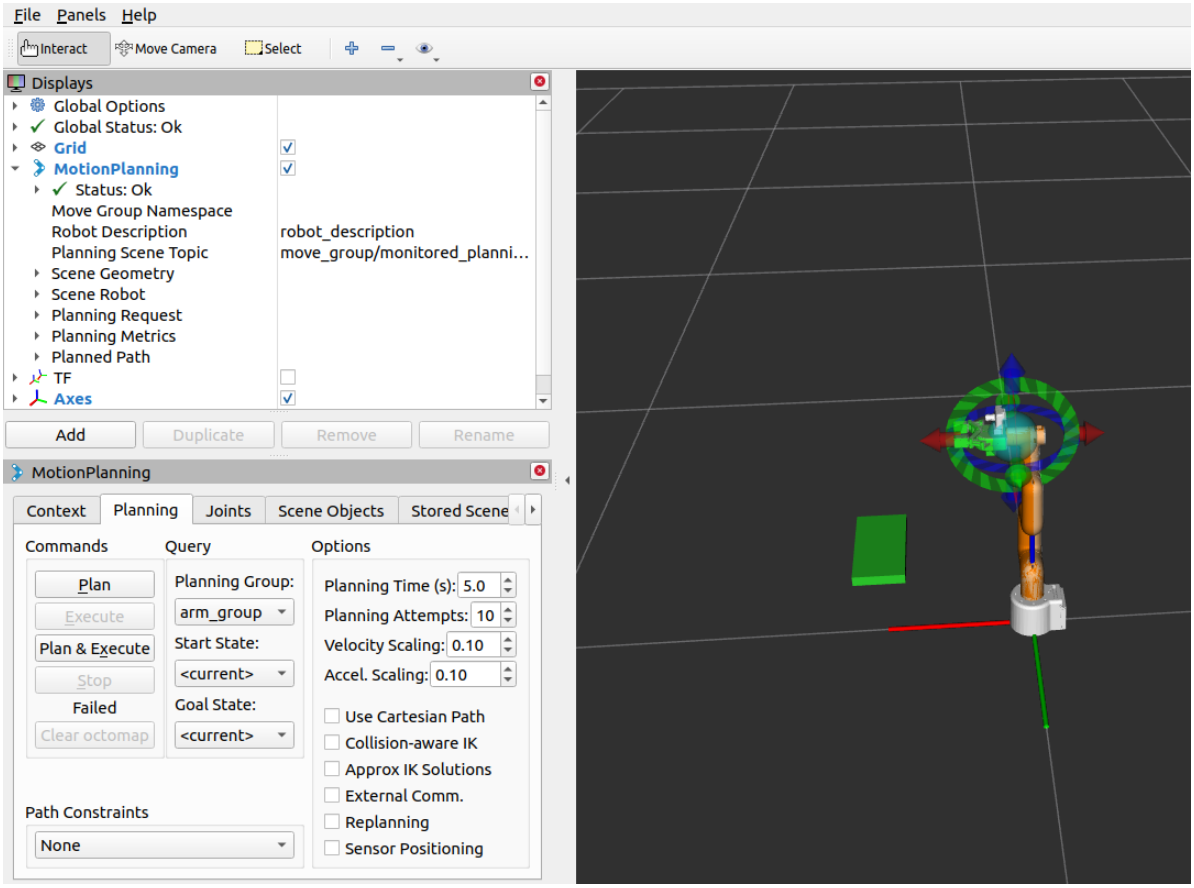
```
sh ~/start_docker.sh
```

- If you are using Jetson Nano board. You need to enter the following command directly.

```
rosrun jetcobot_moveit 05_attached_object.py
```

Code path：~/jetcobot_ws/src/jetcobot_moveit/scripts/05_attached_object.py

Experimental phenomenon: We can see that the robotic arm will make actions to avoid obstacles in RVIZ.



Close the process: Press [ctrl+c].

If it fails to close, press [ctrl+z].