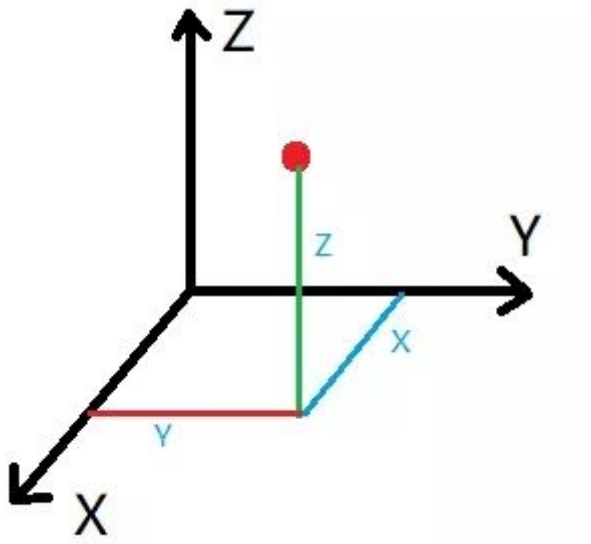
Movelt cartesian path

1. Introduction

The Cartesian coordinate system is a general term for the rectangular coordinate system and the oblique coordinate system.

The Cartesian path is actually the line connecting any two points in space.



2. Start

2.1 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
```

2.2 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
```

2.3 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.

2.4 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.

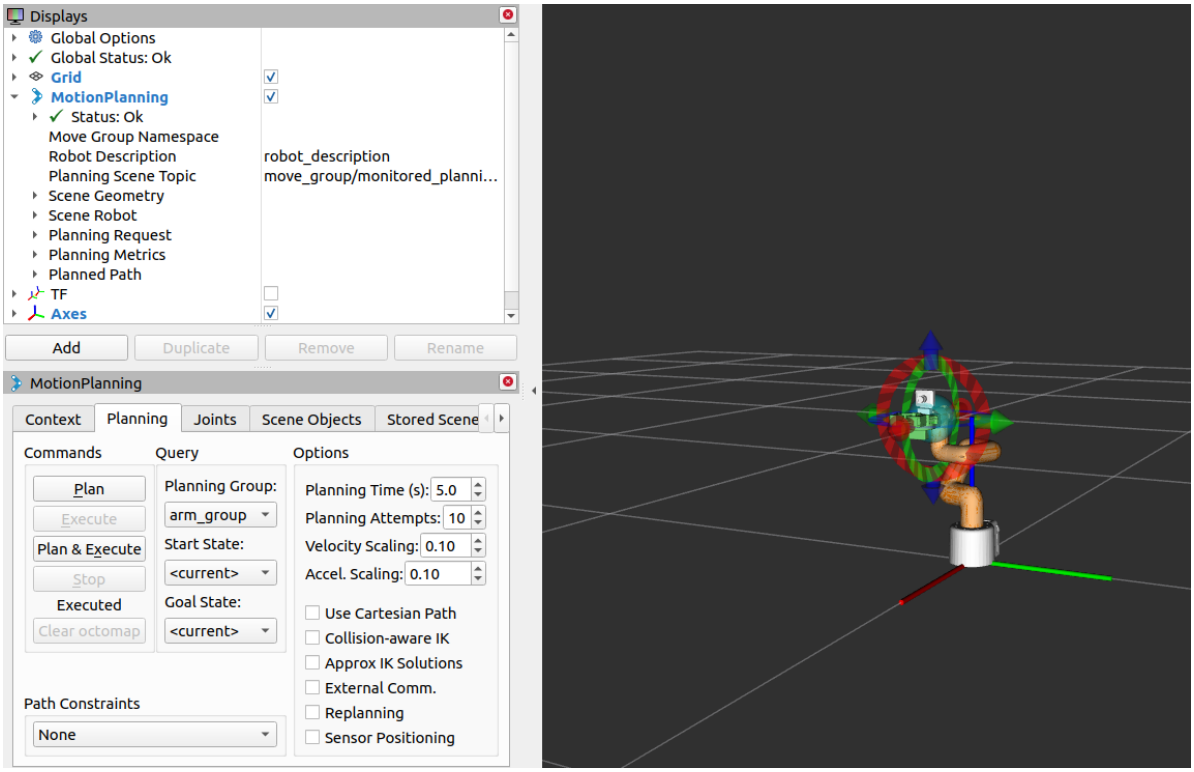
```
sh ~/start_docker.sh
```

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

```
rosrun jetcobot_moveit 04_cartesian.py
```

Code path：~/jetcobot_ws/src/jetcobot_moveit/scripts/04_cartesian.py

Experimental phenomenon: We can see that the robotic arm in rviz will randomly search for the target point and move.



Close the process: Press [ctrl+c].

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