Activities  
> moveit\_setup\_assistant  
Apr 14 13:00  
A  
Movelt Setup Assistant  
×  
Start  
?  
Define Virtual Joints  
Create a virtual joint between the base robot link and an external frame of reference. This allows to place the robot in the  
Self-Collisions  
world or on a mobile platform.  
Virtual Joints  
Virtual Joint Name:  
base\_word\_link  
Planning Groups  
Child Link:  
OO  
ur5\_base\_link  
Robot Poses  
Parent Frame Name:  
End Effectors  
world  
Joint Type:  
Passive Joints  
fixed  
......  
Controllers  
......  
Simulation  
3D Perception  
Author Information  
Configuration Files  
Save  
Cancel  
V visual collision