

The background features a light yellow and white gradient. A faint, stylized illustration of a robotic arm is visible, with its gripper holding a red block labeled '1'. Other blocks are scattered around: a red block labeled '2' on a circular base, a red block labeled '3' with 'REAL' on its side, and two blue blocks labeled 'HELLO' and 'WORLD'. In the bottom left corner, there is a logo consisting of a 3x3 grid of dots followed by the text 'ROS'.

4.4

# Movelt! commander

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- Movelt! command line tool to send motion commands to robot arms.
- Started with the following command  

```
$ rosrun moveit_commander moveit_commander_cmdline.py
```
- Useful to test/check Movelt! configuration and robot motions.

# Movelt! commander - basic commands

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- list all usable commands within Movelt! commander

```
$ help
```

- select the “group” to use

```
$ use <group_name>
```

- plan and execute motion to named joint value targets from **srdf**

```
$ go <named_target>
```

# Movelt! commander - basic commands

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- plan and execute linear motions for robot end effector

```
$ go <up | down | left | right | forward | backward> <distance_in_m>
```

- get current joint state and pose of end effector of active group

```
$ current
```

- execute multiple commands from a script

```
$ load <path_to_script_file/script_file_name>
```

