

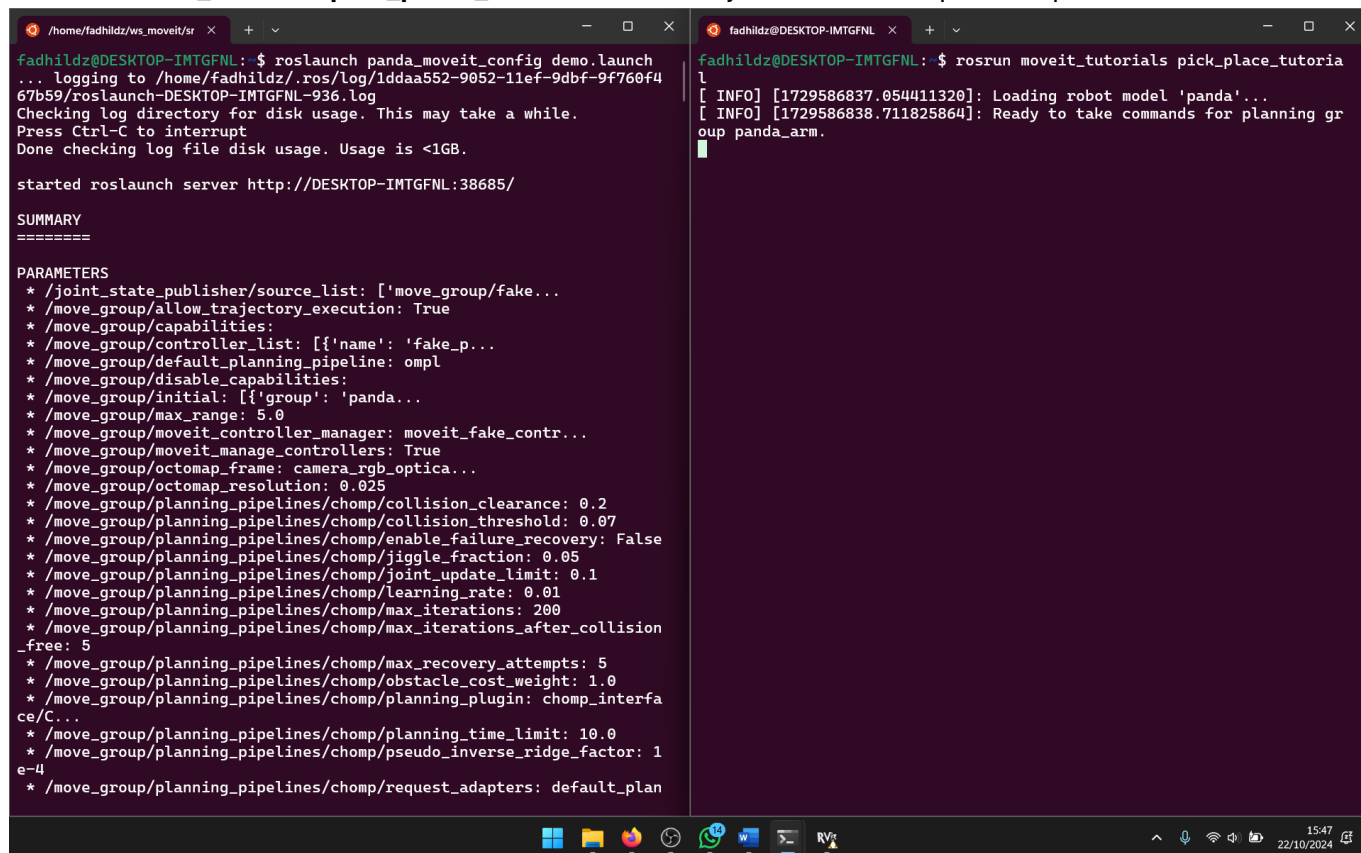
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Pick and Place – MoveIt 1 Noetic

1. Jalankan **roslaunch panda_moveit_config demo.launch** untuk menjalankan RViz dan **roslaunch moveit_tutorials pick_place_tutorial** untuk menjalankan tutorial pick and place.



```
fadhildz@DESKTOP-INTGFLN:~$ roslaunch panda_moveit_config demo.launch
... logging to /home/fadhildz/.ros/log/1ddaa552-9052-11ef-9dbf-9f760f4
67b59/roslaunch-DESKTOP-INTGFLN-936.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://DESKTOP-INTGFLN:38685/

SUMMARY
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PARAMETERS
* /joint_state_publisher/source_list: ['move_group/fake...
* /move_group/allow_trajectory_execution: True
* /move_group/capabilities:
* /move_group/controller_list: [{'name': 'fake_p...
* /move_group/default_planning_pipeline: ompl
* /move_group/disable_capabilities:
* /move_group/initial: [{'group': 'panda...
* /move_group/max_range: 5.0
* /move_group/moveit_controller_manager: moveit_fake_contr...
* /move_group/moveit_manage_controllers: True
* /move_group/octomap_frame: camera_rgb_optica...
* /move_group/octomap_resolution: 0.025
* /move_group/planning_pipelines/chomp/collision_clearance: 0.2
* /move_group/planning_pipelines/chomp/collision_threshold: 0.07
* /move_group/planning_pipelines/chomp/enable_failure_recovery: False
* /move_group/planning_pipelines/chomp/jiggle_fraction: 0.05
* /move_group/planning_pipelines/chomp/joint_update_limit: 0.1
* /move_group/planning_pipelines/chomp/learning_rate: 0.01
* /move_group/planning_pipelines/chomp/max_iterations: 200
* /move_group/planning_pipelines/chomp/max_iterations_after_collision
_free: 5
* /move_group/planning_pipelines/chomp/max_recovery_attempts: 5
* /move_group/planning_pipelines/chomp/obstacle_cost_weight: 1.0
* /move_group/planning_pipelines/chomp/planning_plugin: chomp_interfa
ce/C...
* /move_group/planning_pipelines/chomp/planning_time_limit: 10.0
* /move_group/planning_pipelines/chomp/pseudo_inverse_ridge_factor: 1
e-4
* /move_group/planning_pipelines/chomp/request_adapters: default_plan

fadhildz@DESKTOP-INTGFLN:~$ roslaunch moveit_tutorials pick_place_tutorial
[ INFO] [1729586837.054411320]: Loading robot model 'panda'...
[ INFO] [1729586838.711825864]: Ready to take commands for planning gr
oup panda_arm.
```

2. Robot akan bergerak sesuai instruksi.

