

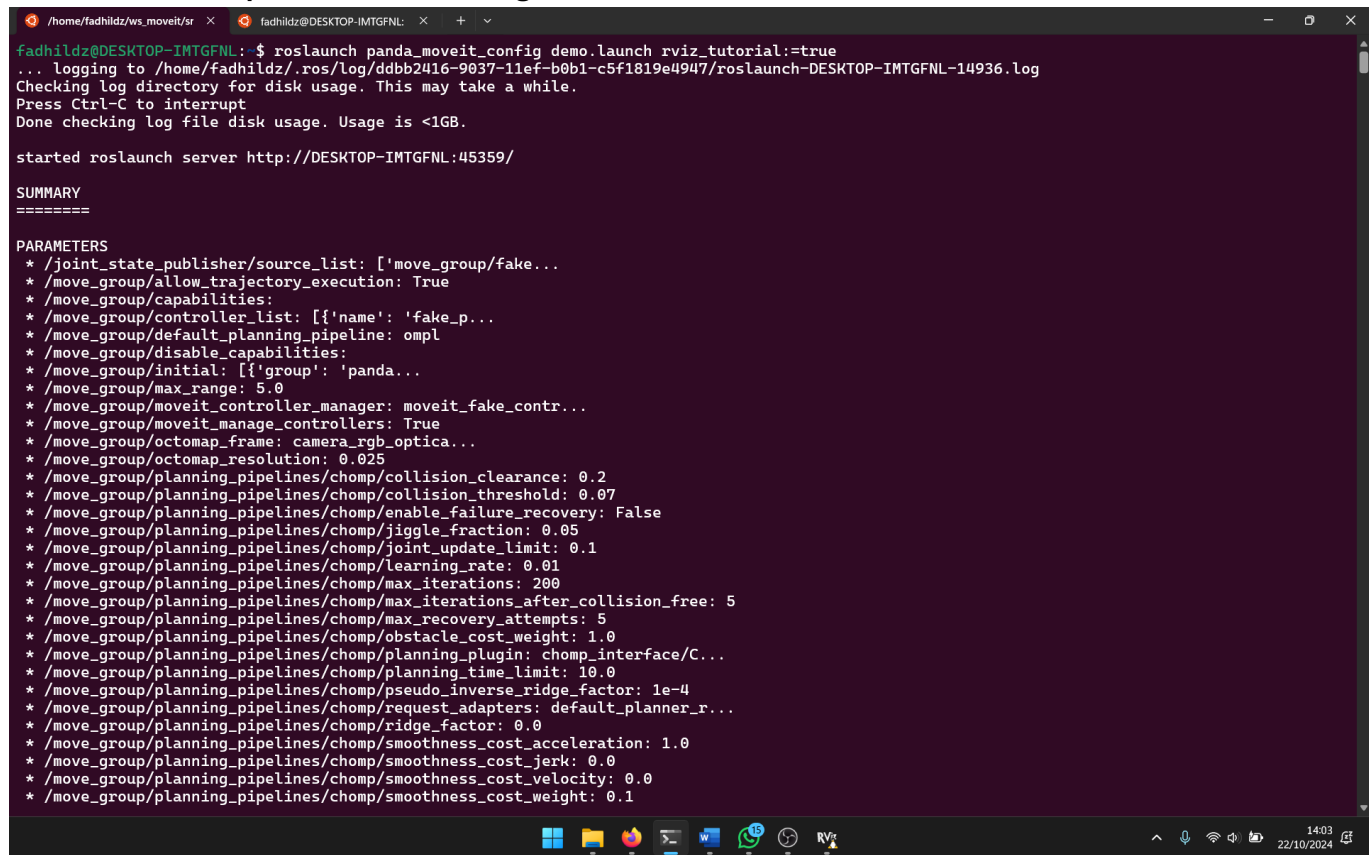
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Kelas : TK-45-G09

## MoveIt Quickstart in RViz – MoveIt 1 Noetic

### 1. `roslaunch panda_moveit_config demo.launch rviz_tutorial:=true` untuk membuka Rviz.



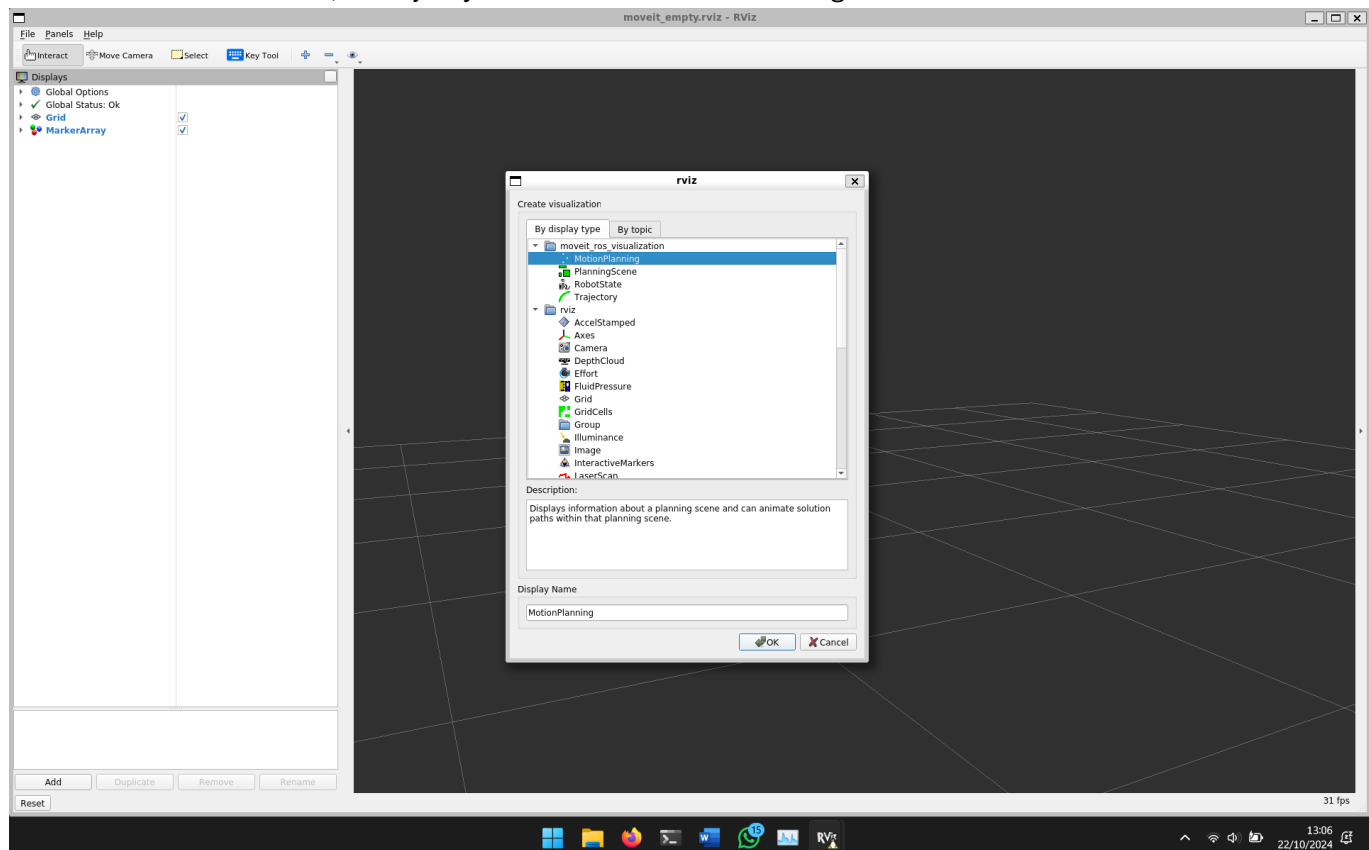
```
fadhildz@DESKTOP-IMTGFNL:~$ roslaunch panda_moveit_config demo.launch rviz_tutorial:=true
... logging to /home/fadhildz/.ros/log/ddbb2416-9037-11ef-b0b1-c5f1819e4947/roslaunch-DESKTOP-IMTGFNL-14936.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://DESKTOP-IMTGFNL:45359/

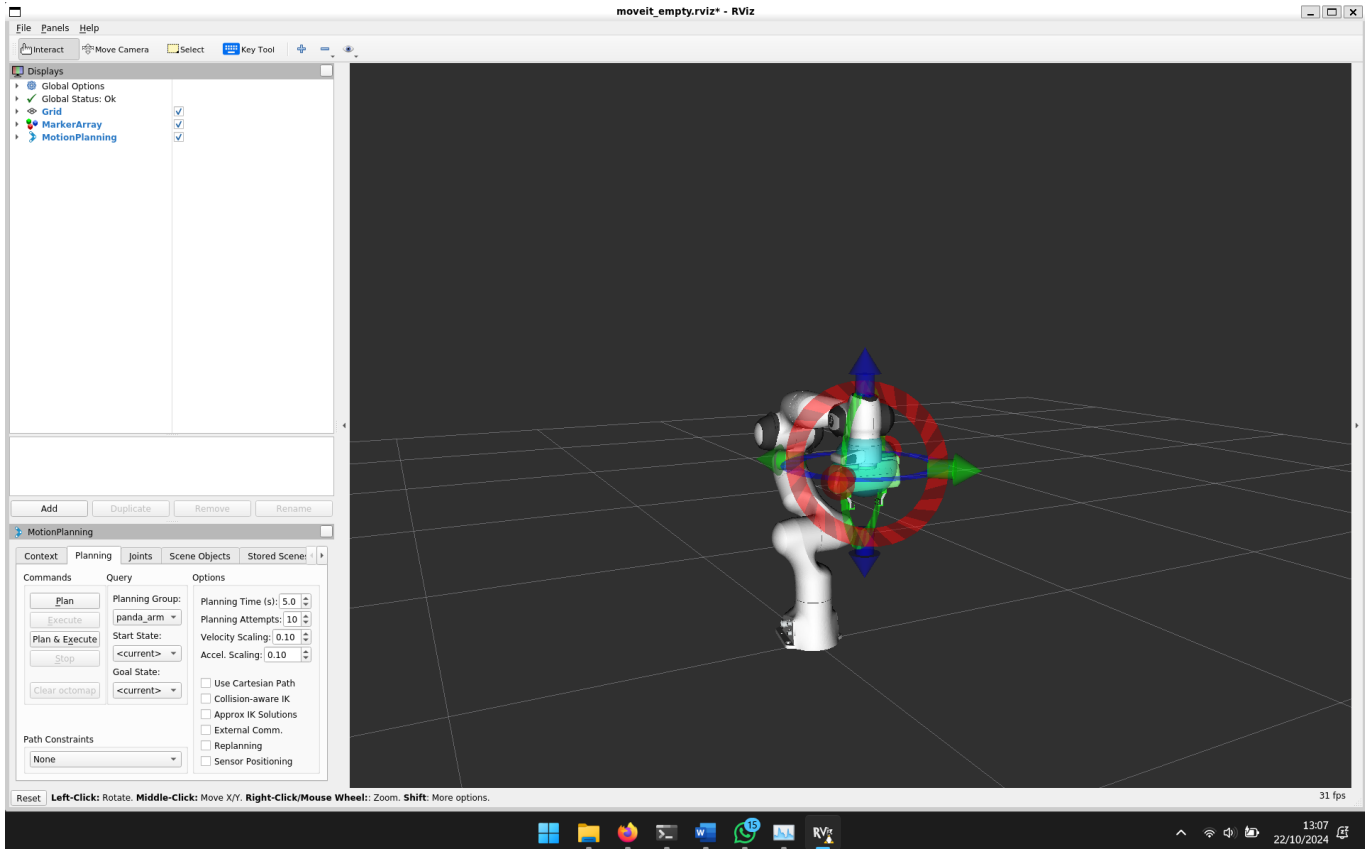
SUMMARY
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PARAMETERS
* /joint_state_publisher/source_list: ['move_group/fake...
* /move_group/allow_trajectory_execution: True
* /move_group/capabilities:
* /move_group/controller_list: [{'name': 'fake_p...
* /move_group/default_planning_pipeline: ompl
* /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_interface/C...
* /move_group/planning_pipelines/chomp/planning_time_limit: 10.0
* /move_group/planning_pipelines/chomp/pseudo_inverse_ridge_factor: 1e-4
* /move_group/planning_pipelines/chomp/request_adapters: default_planner_r...
* /move_group/planning_pipelines/chomp/ridge_factor: 0.0
* /move_group/planning_pipelines/chomp/smoothness_cost_acceleration: 1.0
* /move_group/planning_pipelines/chomp/smoothness_cost_jerk: 0.0
* /move_group/planning_pipelines/chomp/smoothness_cost_velocity: 0.0
* /move_group/planning_pipelines/chomp/smoothness_cost_weight: 0.1
```

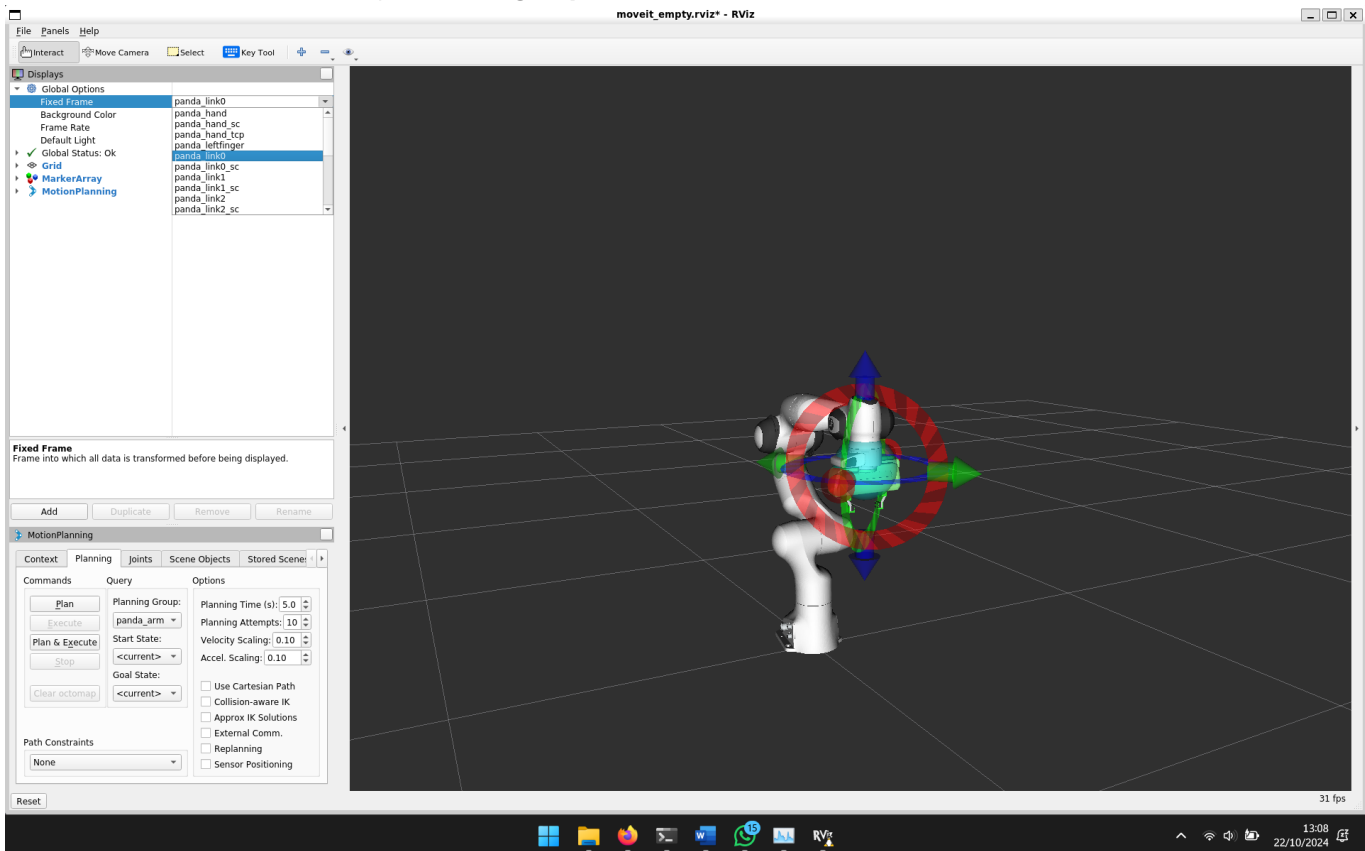
### 2. RViz akan terbuka, selanjutnya tambahkan MotionPlanning.



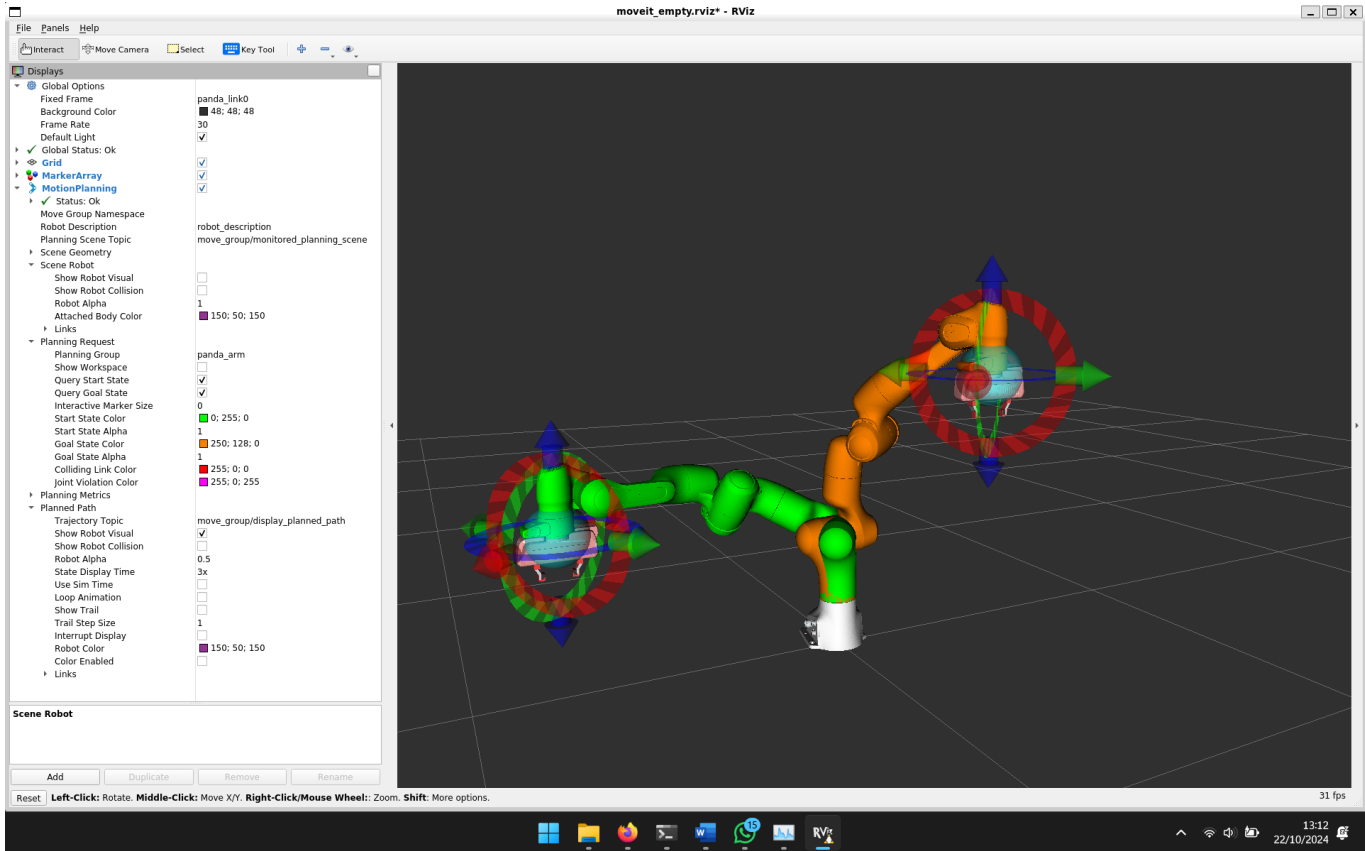
### 3. Robot panda\_arm akan muncul di layar.



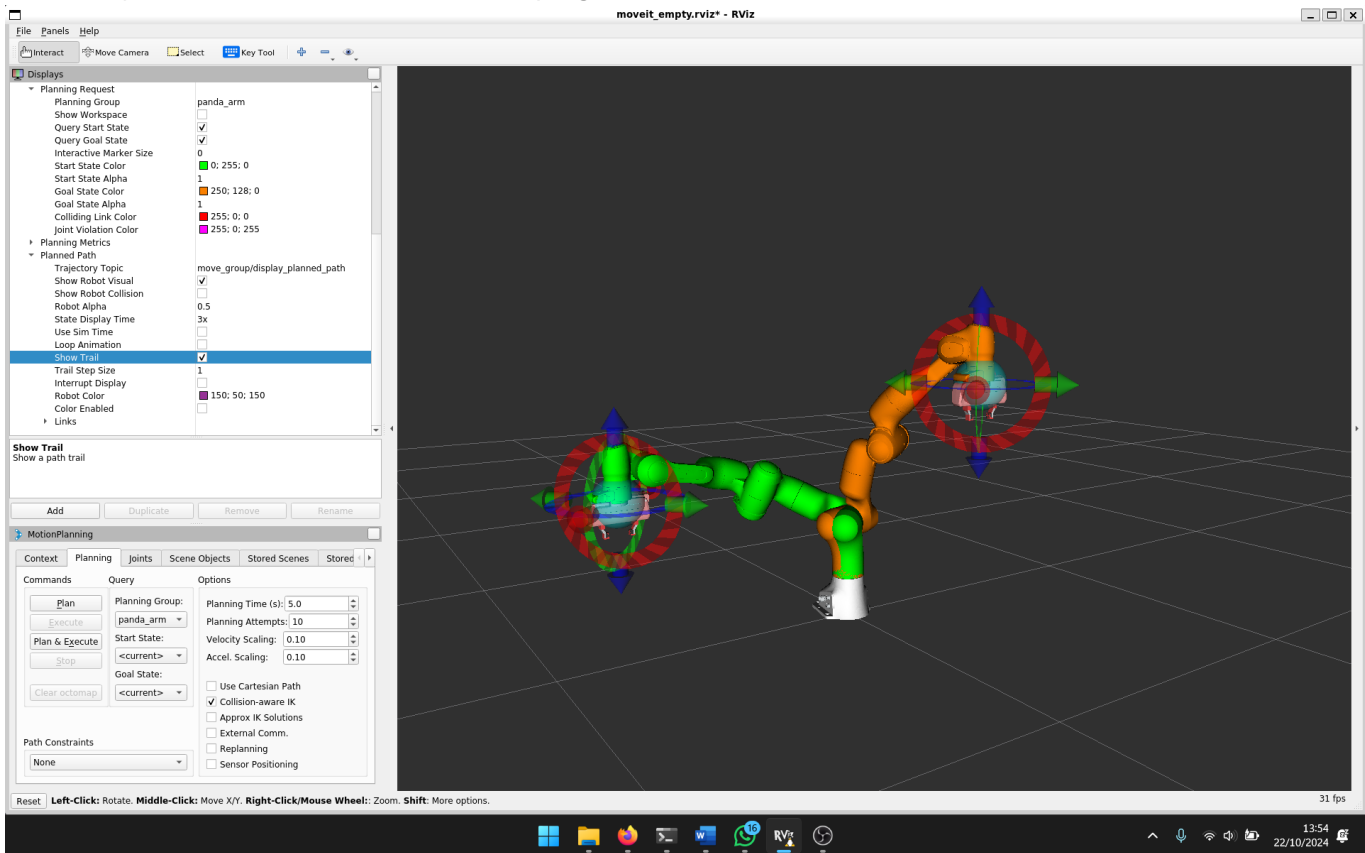
### 4. Pastikan fixed frame nya di setting ke **panda\_link0**



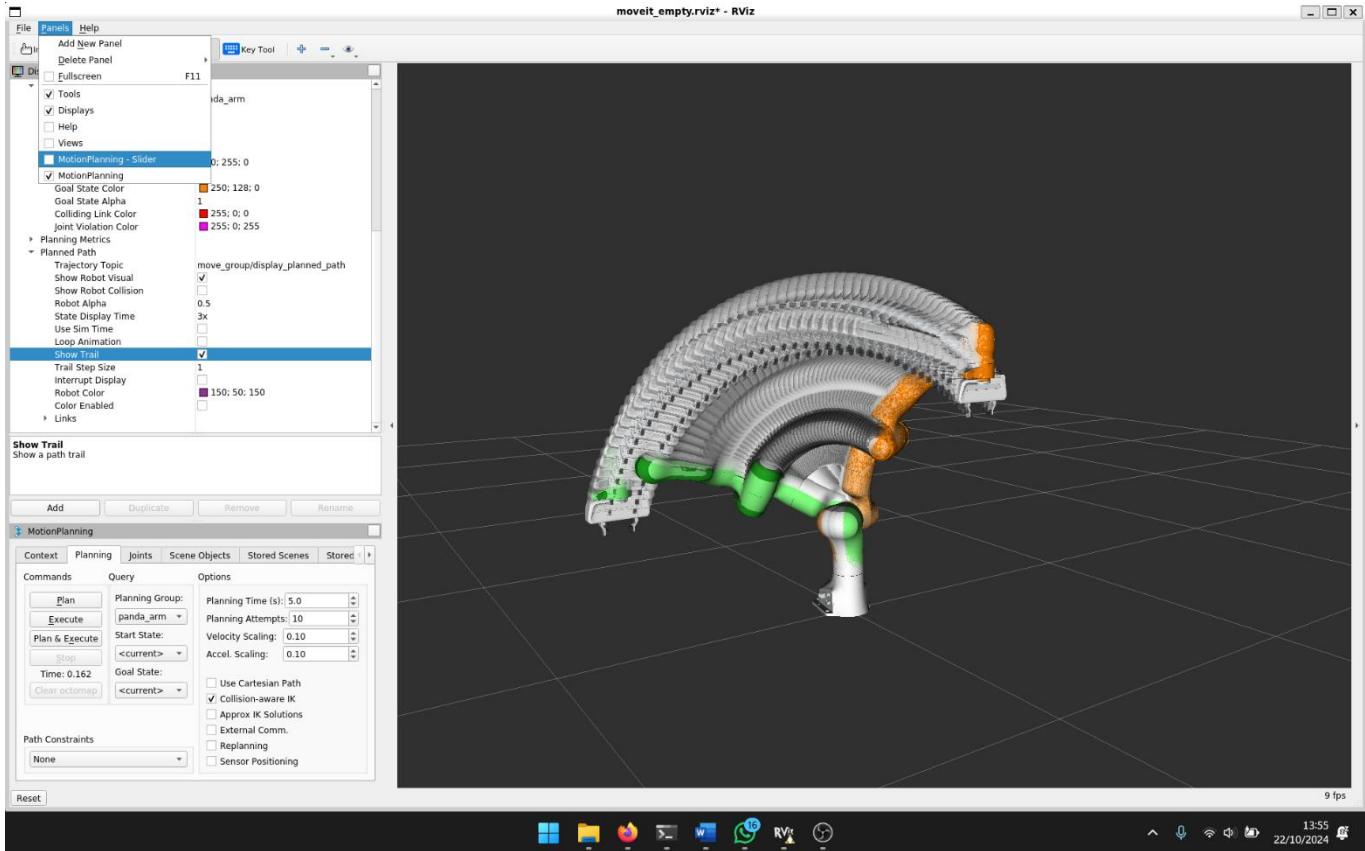
5. Setting sesuai dengan instruksi, lalu ubah posisi query start dan query goal nya.



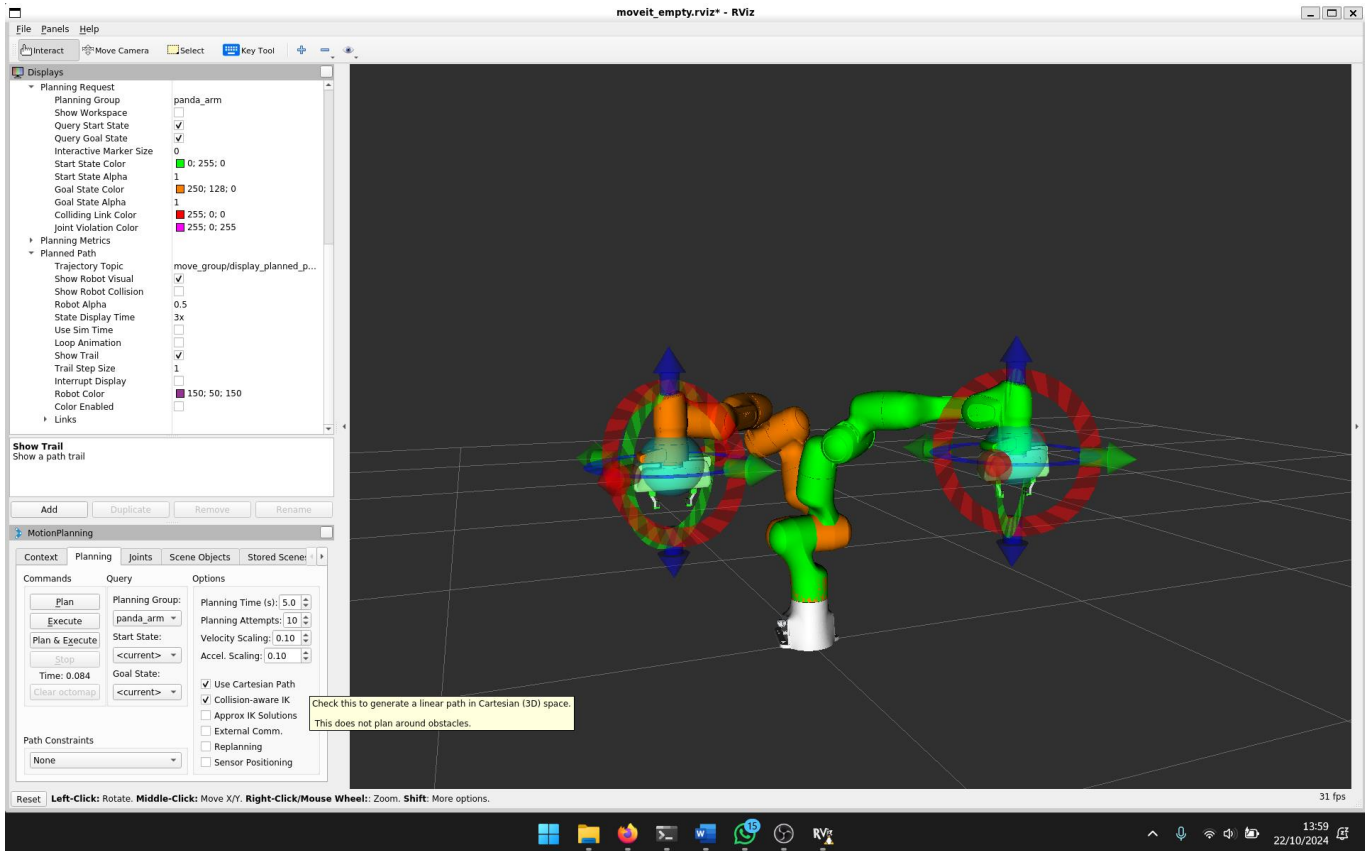
6. Nyalakan show trail untuk melihat pergerakan robot



7. Klik plan, maka robot akan bergerak dari query start (hijau) ke query goal (orange)



8. Nyalakan use cartesian path untuk melihat path cartesian lalu klik plan



## 9. Akan terlihat trail dari cartesian path.

