

roslaunch simple_example sim.launch

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Applications Places /home/guillaume/roscode/catkin_ws3/src/kuka-lwr-ros/kuka_planning_interface/simple_example/launch/client.launch http://192.168.0.1:11311
/home/guillaume/roscode/catkin_ws3/src/kuka-lwr-ros/kuka_planning_interface/simple_example/launch/sim.launch http://192.168.0.1:11311 209x25
[ INFO] [1450290397.433016986, 0.282000000]: Number of segments: 7
[ INFO] [1450290397.433036452, 0.282000000]: Number of joints in chain: 7
[ INFO] [1450290397.433069307, 0.282000000]: Getting limits for joint: lwr_6_joint
[ INFO] [1450290397.433095391, 0.282000000]: Getting limits for joint: lwr_5_joint
[ INFO] [1450290397.433118225, 0.282000000]: Getting limits for joint: lwr_4_joint
[ INFO] [1450290397.433138152, 0.282000000]: Getting limits for joint: lwr_3_joint
[ INFO] [1450290397.433158828, 0.282000000]: Getting limits for joint: lwr_2_joint
[ INFO] [1450290397.433180196, 0.282000000]: Getting limits for joint: lwr_1_joint
[ INFO] [1450290397.433202679, 0.282000000]: Getting limits for joint: lwr_0_joint
[ INFO] [1450290397.433222859, 0.282000000]: Getting joint handles
[ INFO] [1450290397.433242018, 0.282000000]: lwr_0_joint type: RotAxis
[ INFO] [1450290397.433279152, 0.282000000]: lwr_1_joint type: RotAxis
[ INFO] [1450290397.433306759, 0.282000000]: lwr_2_joint type: RotAxis
[ INFO] [1450290397.433332531, 0.282000000]: lwr_3_joint type: RotAxis
[ INFO] [1450290397.433355893, 0.282000000]: lwr_4_joint type: RotAxis
[ INFO] [1450290397.433380087, 0.282000000]: lwr_5_joint type: RotAxis
[ INFO] [1450290397.433402673, 0.282000000]: lwr_6_joint type: RotAxis
[ INFO] [1450290397.433426604, 0.282000000]: Number of joints in handle = 7
[ INFO] [1450290397.433446577, 0.282000000]: kdl_chain.getNrOfJoints: 7
[ INFO] [1450290397.433463357, 0.282000000]: Finished Kinematic Base init
[ INFO] [1450290397.433526737, 0.282000000]: finished joint position impedance init
[INFO] [WallTime: 1450290397.444123] [0.288000] Controller Spawner: Loaded controllers: one_task_inverse_kinematics, joint_position_impedance_controller
The ControlStrategy didn't changed, it is already: 10
[INFO] [WallTime: 1450290397.446157] [0.289000] Started controllers: kuka_joint_state_controller
```

```
/home/guillaume/roscode/catkin_ws3/src/kuka-lwr-ros/kuka_planning_interface/simple_example/launch/server.launch http://192.168.0.1:11311
guillaume@guillaume-desktop:~$ roslaunch simple_example server.launch
... logging to /home/guillaume/.ros/log/89cb7ce4-a422-11e5-a6c6-7824af337b03/roslaunch-guillaume-desktop-22759.log
Checking log directory for disk usage. This may take awhile.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://192.168.0.1:48269/

SUMMARY
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PARAMETERS
* /kuka_server/action_server_name: kuka_server
* /roscdistro: indigo
* /rosversion: 1.11.16

NODES
/
  kuka_server (simple_example/server_action_node)

ROS_MASTER_URI=http://192.168.0.1:11311

core service [/rosout] found
process[kuka_server-1]: started with pid [22778]
[ INFO] [1450290426.147080416]: Initializing Server
--- parameters ---
[ INFO] [1450290426.168005026]: action SERVER started
```

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/home/guillaume/roscode/catkin_ws3/src/kuka-lwr-ros/kuka_planning_interface/simple_example/launch/client.launch http://192.168.0.1:11311
KUKA PLANNING INTERFACE
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