



UR5 Simulation notes

1. Introduction

This document describes several dependencies to be fulfilled to have the UR5 Gazebo simulation running.

2. Dependencies

- Gazebo_ros_pkgs (this package is already installed)
- universal_robots (this package has Moveit configuration packages for different Universal robots)

```
$ cd moveit_ws/src
$ git clone https://github.com/ros-industrial/universal\_robot
$ cd ..
$ catkin_make
$ source devel/setup.bash
```

3. Startup

Open each command below in a new terminal:

```
$ roslaunch ur5_moveit_config_pkg ur5_gazebo.launch
$ roslaunch ur5_moveit_config_pkg ur5_moveit_planning_execution.launch
sim:=true
$ rviz
```

4. RViz configuration

1. Add the “Motion Planning” type into RViz
2. Set the fixed frame to “world”

