



MASCOR

Mobile Autonomous Systems
and Cognitive Robotics



Denso Simulation notes

1. Introduction

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

2. Dependencies

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

```
$ cd moveit_ws/src
$ git clone https://github.com/ipa-nhg-hd/denso\_robot\_ros
$ cd ..
$ catkin_make
$ source devel/setup.bash
```

3. Startup

The following command launches gazebo, moveit-related launch files and RViz

```
$ roslaunch denso_moveit_config_pkg denso_robot_gazebo.launch
$ roslaunch denso_moveit_config_pkg denso_moveit.launch sim:=true
```

4. RViz configuration

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