Quickstart Guide

workspace : evers\_ws

1. Source   
   cd ../evers\_ws  
   source devel/setup.bash
2. Launch openni2

roslaunch openni2\_launch openni2.launch

1. Launch Rqt-reconfigure and check in camera>driver “depth\_registration”

rosrun rqt\_reconfigure rqt\_reconfigure

camera > driver > cocher « depth\_registration »

1. Launch ORK-tabletop

rosrun object\_recognition\_core detection -c `rospack find object\_recognition\_tabletop`/conf/detection.table.ros.ork

1. Launch

roslaunch '/home/astrostudent/evers\_ws/launch/evers\_ws\_recognition.launch'

1. Launch Rviz and display : filtered\_cloud(Pointcloud2) to check what clusters are being processed

DetectedObjectsMarkers(Marker) to see what and where clusters have been detected

rviz

*Empty the database*

1. To train (fill the db with the scene\_objects)

rosservice call /object\_manager\_srv train

1. Label the objetcs in db (in info.txt)
2. You can optionally change any param in the launch file situated in the root directory of the project, you ll need to relaunch after any changes
3. To launch a detection (Don’t forget to source)

rostopic pub discrim\_status object\_discrimination/DetectionInput "{'mode':'detect','label':['can']}"

1. If the discrimination node launch is commented in launch file , launch the node with this command line:

source devel/setup.bash

rosrun object\_discrimination Objectdiscrimination