

Readme:

1. I used move it setup assistant to set the panda robot.
2. Used c++ script to move the robot from home_state to goal state1 and goal state2.
3. In c++ script the orientation and position of goal states are given.
4. Used close_gripper and open_gripper to handle gripper conditions.

LIBS:

1. Chrono -> For sleep time delay
2. Memory -> used for shared and unique pointers
3. Rclcpp -> ROS2 nodes
4. Moveit_group_interface -> panda robot controlling

Running cmd:

1. `ros2 run package_120511257 package_120511257` → my package
2. `ros2 launch manoj's_panda demo.launch.py` → running
panda rviz
3. `ros2 launch moveit_setup_assistant setup_assistant.launch.py` → move
it setup assistant