



```

Inmo@Inmo-workstation: ~
Inmo@Inmo-workstation: ~ 57x35
Position Control: (NB: Increment = 0.01 (m))
- Forward/Backward/Left/Right (x-y-axis): u / j / h / k
- Up/Down (z-axis): t / g
Orientation Control: (NB: Increment = pi/50 (rad))
- Pitch Up/Down : w / s
- Roll Left/Right: a / d
- Yaw Left/Right : q / e
-----
Pose Command : 1, 2
-----
anything else : stop or CTRL-C to quit
=====
=> Key input = h
hhhh
=====
Reading from the keyboard and Publishing to move UR5!
-----
Position Control: (NB: Increment = 0.01 (m))
- Forward/Backward/Left/Right (x-y-axis): u / j / h / k
- Up/Down (z-axis): t / g
Orientation Control: (NB: Increment = pi/50 (rad))
- Pitch Up/Down : w / s
- Roll Left/Right: a / d
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-----
Pose Command : 1, 2
-----
anything else : stop or CTRL-C to quit
=====
=>
[ INFO ] [1538565461.385548173, 176.396000000]: gazebo_ros_control plugin is waiting for model URDF in parameter [robot_description] on the ROS param server.
[ INFO ] [1538565461.445235506, 176.396000000]: Loaded gazebo_ros_control.
dGain after overloading: 0.5
dGain after overloading: 0.5
dGain after overloading: 0.5
dGain after overloading: 0.5
dGain after overloading: 0.5
[spawn_gazebo_model-4] process has finished cleanly
log file: /home/inmo/.res/log/e6abd4c-c6fd-11e8-9215-e0b432900f9/spawn_gazebo_model-4*.log
[ INFO ] [1538565461.498499718, 176.426000000]: waitForService: Service [/gazebo/set_physics_properties] is now available.
[ INFO ] [1538565461.609736725, 176.517000000]: Physics dynamic reconfigure ready.
Loaded arm controller
Loaded joint state controller
Started [arm controller] successfully
Started [joint state controller] successfully

```