

Fig 1. Wired Connection

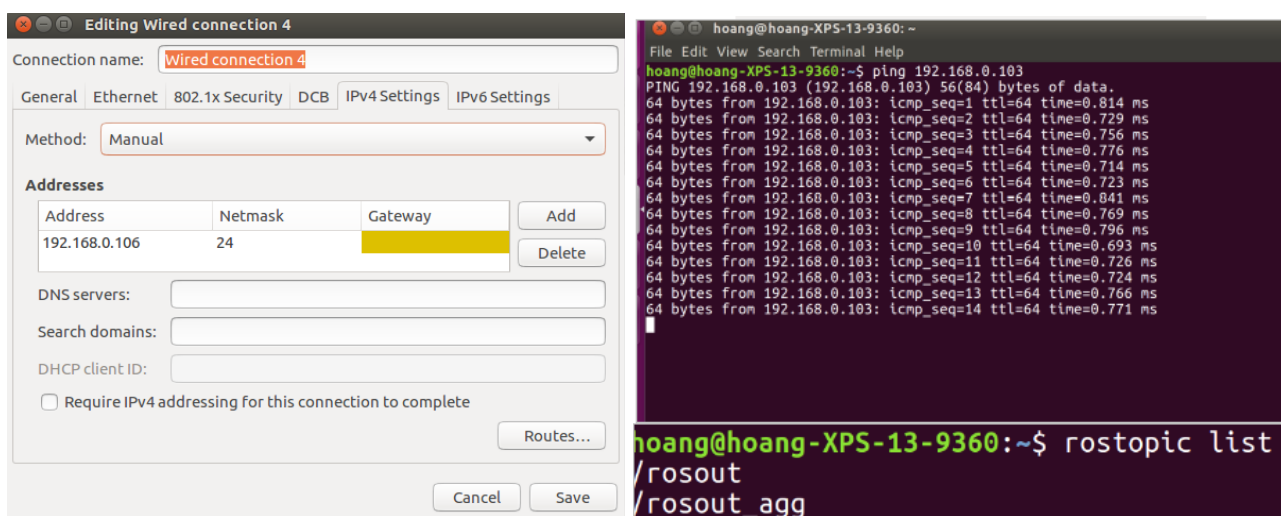


Fig 2. Set IP and Check Connection

```
# remotely ros Robotlab
export ROS_IP=192.168.0.106 # it's your laptop's IP
export ROS_MASTER_URI=http://192.168.0.103:11311 #it's the serve
```

Fig 3. Change .bashrc file in the laptop

```
$ catkin_make -DFranka_DIR=/home/frankanuc03/libfranka/build
$ roslaunch franka_tminplan joint_point_to_point_motion_my.launch
$ roslaunch franka_example_controllers model_example_controller_with_gripper.launch robot_ip:=172.16.0.103
```