

ROS

Install the ros-jade-schunk-canopen-driver (for jade...)

```
sudo apt-get install ros-jade-schunk-canopen-driver
```

At least for jade you need to clone from github schunk_grippers (not from apt-get) - put in your catkin workspace:

```
git clone https://github.com/SmartRoboticSystems/schunk_grippers.git
```

Get our custom packages for the table setup here - put in your catkin workspace.

For students of the robotics group clone from our git:

```
git clone git@robotics.shanghaitech.edu.cn:schunk_table
```

For other students clone from the webserver:

```
git clone https://robotics.shanghaitech.edu.cn/static/git/schunk_table.git
```

Don't forget to source in the catkin workspace...

Important files

lwa_description has the custom robot descriptions (urdf) and the launchfile that loads those together with the driver for the robot.

Startup

```
roslaunch lwa_description robot.launch  
  
roslaunch lwa_moveit_config move_group.launch  
  
roslaunch lwa_moveit_config moveit_rviz.launch
```

For now (until we have a better power supply) select: Velocity Scaling 0.2 and Accelerator Scaling 0.01!

How to program the arm:

http://docs.ros.org/indigo/api/moveit_tutorials/html/index.html

API:http://docs.ros.org/jade/api/moveit_ros_planning_interface/html/classmoveit_1_1planning__interface_1_1MoveGroup.html

Example program that should compile with ROS jade is in the git:

```
schunk_table/schunk_table_example
```