



# ROBOT ARM JOINT CONTROL

# Robot Arm Joint Control

## GUI Interface

- `$ cd ~/catkin_ws/src/basic_function_packages/dynamixel_hr/`
- `$ python ToolDynamixelLab.py`

## Bring up

- `$ roslaunch rhomeedu_arm arm.launch`

## ROS topics

- `/waist_controller/command`
- `/shoulder_controller/command`
- `/elbow_controller/command`
- `/wrist_controller/command`
- `/hand_controller/command`

## Moving the joints

- `$ rostopic pub -1 /waist_controller/command std_msgs/Float64 -- 0.3`
- `$ rostopic pub -1 /shoulder_controller/command std_msgs/Float64 -- 0.3`
- `$ rostopic pub -1 /elbow_controller/command std_msgs/Float64 -- 0.3`
- `$ rostopic pub -1 /wrist_controller/command std_msgs/Float64 -- 0.3`
- `$ rostopic pub -1 /hand_controller/command std_msgs/Float64 -- 0.3`

## Source code implementation

- Bring up - `$ roslaunch rhomeedu_arm arm.launch`
- Arm movements - `$ rosrn rhomeedu_arm arm.py | dance_arm.py (pub "dance arm")`