The TurtleBot 3 Burger itself does not come with a built-in gripper arm, so you would need to choose and integrate a compatible gripper arm module.Here is a code structure that demonstrates the control of a gripper arm using ROS:

import rospy

from gripper\_msgs.msg import GripperCommand

# Define gripper control function

def control\_gripper(opening\_width):

    # Create a GripperCommand message

    gripper\_cmd = GripperCommand()

    gripper\_cmd.position = opening\_width

    # Publish the command to the gripper topic

    gripper\_pub.publish(gripper\_cmd)

# Main function

if \_\_name\_\_ == '\_\_main\_\_':

    try:

        # Initialize the ROS node

        rospy.init\_node('gripper\_control\_node')

        # Create a publisher for the gripper control topic

        gripper\_pub = rospy.Publisher('gripper\_command\_topic', GripperCommand, queue\_size=10)

        # Set the desired opening width for the gripper (adjust as needed)

        opening\_width = 0.05

        # Control the gripper arm

        control\_gripper(opening\_width)

        # Wait for a moment to allow the gripper action to complete

        rospy.sleep(1.0)

        # Set a different opening width for releasing the object (adjust as needed)

        release\_width = 0.08

        # Control the gripper to release the object

        control\_gripper(release\_width)

    except rospy.ROSInterruptException:

        pass