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Low Level Controls

Please report all bugs and issues to the [GitHub Issue Tracker](#). For ROS-related questions visit [ROS Answers](#) or contact [Dave Coleman](#).

Launch ClamArm Stack – Live

To connect and control the physical arm you first need to launch the basic controllers using the following clam.launch command. Then you can optionally secondary launch the visualizer and arm navigation stack.

```
roslaunch clam_bringup clam.launch
```

Send Basic Commands

The debug commands are located in the clam_controller/scripts folder. The follow is a list of some of the commands you can send to the arm to control it

CD To Command Scripts Directory

```
roscd clam_controller/scripts
```

Send Lists of Movement Commands

```
python pose_animate.py
```

```
python pose_cobra.py
```

```
python pose_zero.py
```

```
python pose_sleep.py
```

```
python pose_jaw.py
```

```
python gripper_open.py
```

```
python gripper_close.py
```

Change Torque, Compliance Margin and Compliance Slope (follow instructions on screen)

```
python set_all_torque.py
```

```
python set_all_compliance_margin.py
```

```
python set_all_compliance_slope.py
```

```
python set_all_velocity.py
```

~~**Record and Playback a Sequence of Movements**~~ Currently not working

```
python sequence_record.py
```

```
python sequence_play.py
```

Low-Level Controls of Servos

Output Status Information of Particular Servo

```
rostopic echo /shoulder_pan_controller/state
```

Send Command to Individual Servo

```
rostopic pub -1 /gripper_roll_controller/command std_msgs/Float64 -- 1.0
```

Debug Tools

```
rxgraph
```

```
rxconsole
```

```
roslaunch runtime_monitor monitor
```

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