

# ROS Packages for Mover4 and Mover6 Robot Arms

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## 1. Summary

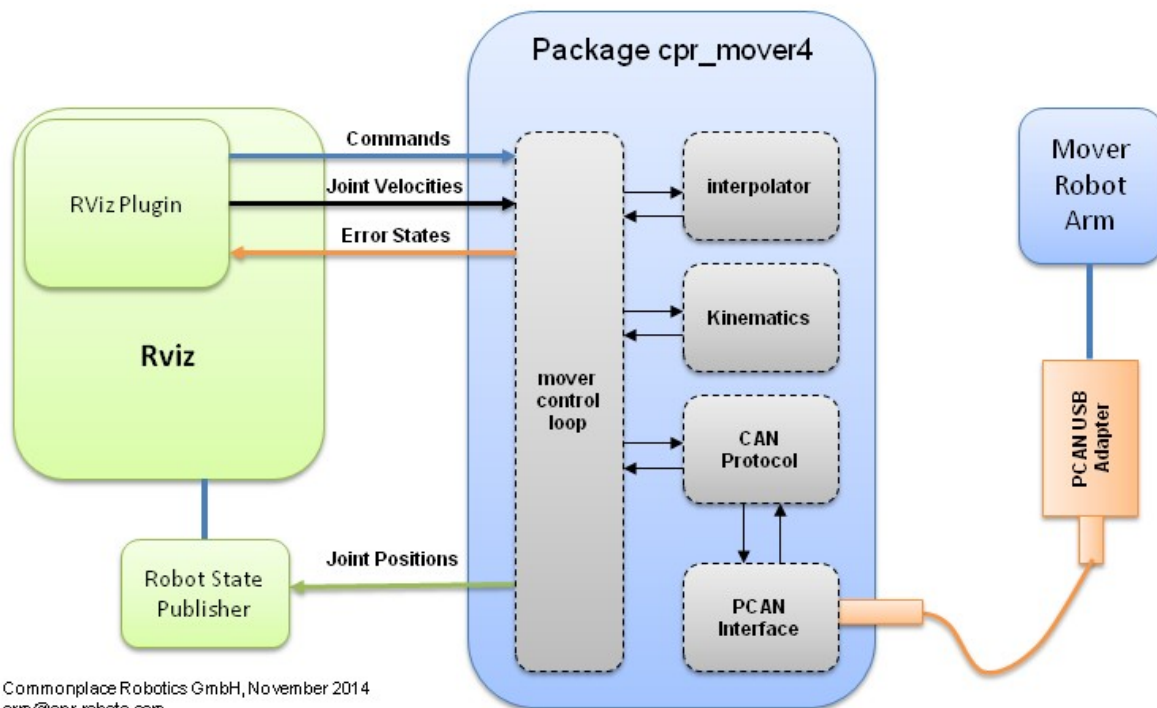
The robot package (cpr\_mover) and the RViz plugin (cpr\_rviz\_plugin) allow to integrate the Mover4 and Mover6 robot arms into ROS environments. An integrated JointTrajectoryAction server allows to perform MoveIt generated motions.

## 2 Tested Environments:

- ROS Indigo, Ubuntu 14.04 LTS

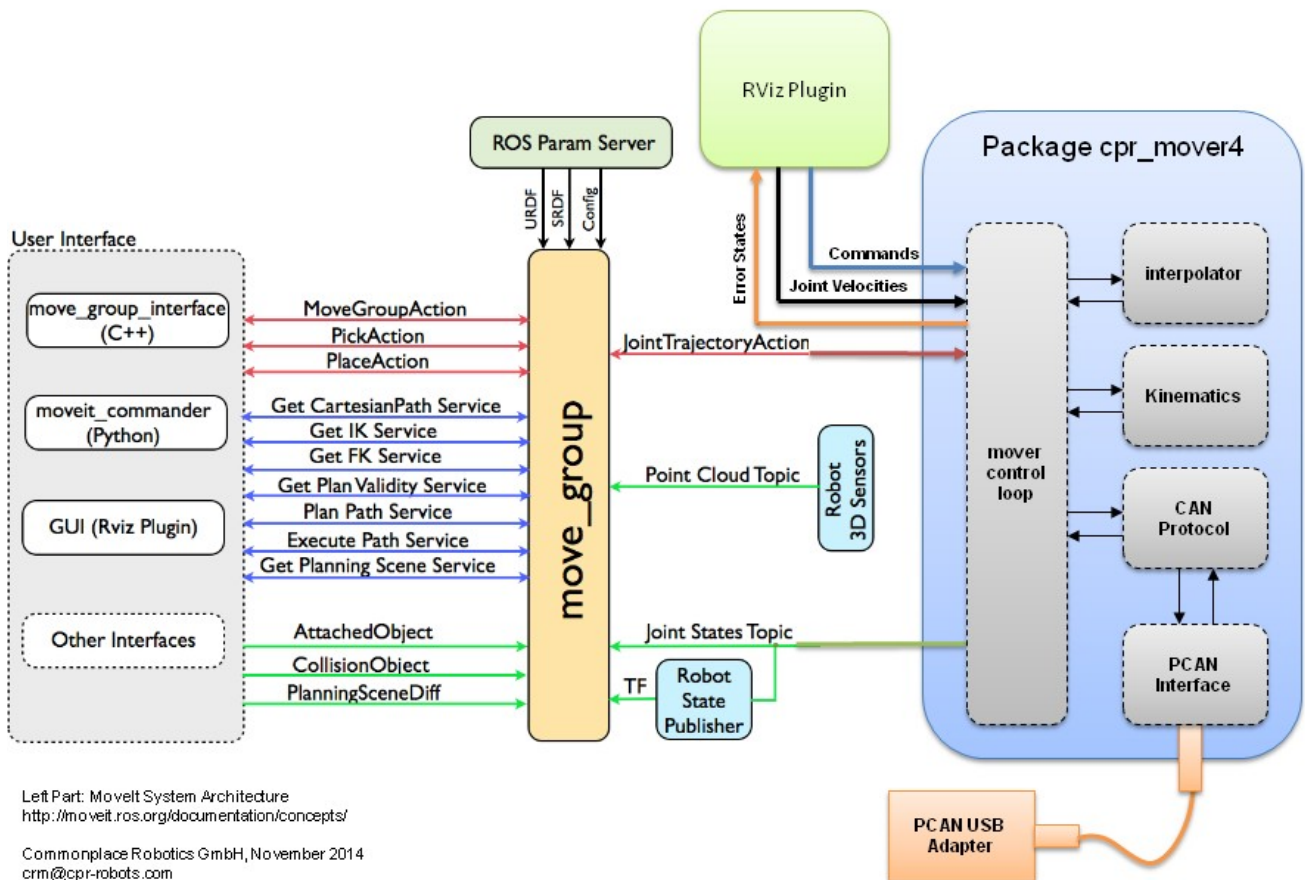
## 3 Architecture

The standard architecture consists of the core, RViz and the cpr\_mover node.



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The interaction with MoveIt is shown in the following slide.



## 2. Download & Installation

### 2 Package cpr\_mover

Download at [http://www.github.com/CPR-Robots/cpr\\_mover](http://www.github.com/CPR-Robots/cpr_mover)

Save in your catkin-src directory, e.g. `~/catkin_ws/src/cpr_mover`

Compile with `catkin_make`

### 3 Plugin cpr\_rviz\_plugin

Download at [http://www.github.com/CPR-Robots/cpr\\_rviz\\_plugin](http://www.github.com/CPR-Robots/cpr_rviz_plugin)

Save in your ROS workspace, e.g. `~/ros-workspace/cpr_rviz_plugin`

Compile with `rosmake`

### 4 Peak PCAN USB-Adapter

The robot arm is connected by a Peak Systeme PCAN-USB adapter. To use the adapter the according driver needs to be installed:

- Download the current driver package from Peak

- Extract driver package
- change into the directory, e.g. `cd peak-linux-driver-7.10`
- `make clean`
- We want to install the chardev version of the driver: `make NET=NO_NETDEV_SUPPORT`
- `sudo make install`
- `reboot`
- the command `cat /proc/pcan` should show:

```
*----- PEAK-System CAN interfaces (www.peak-system.com) -----
*----- Release_20140121_n (7.10.0) Mar  3 2014 14:13:14 -----
*----- [mod] [isa] [pci] [dng] [par] [usb] [pcc] -----
*----- 1 interfaces @ major 249 found -----
*n -type- ndev --base-- irq --btr- --read-- --write- --irqs-- -errors- status
32  usb -NA- ffffffff 255 0x001c 00000000 00000000 0000000c 00000000 0x0000
```

Especially below the `ndev` word there should be `-NA-`

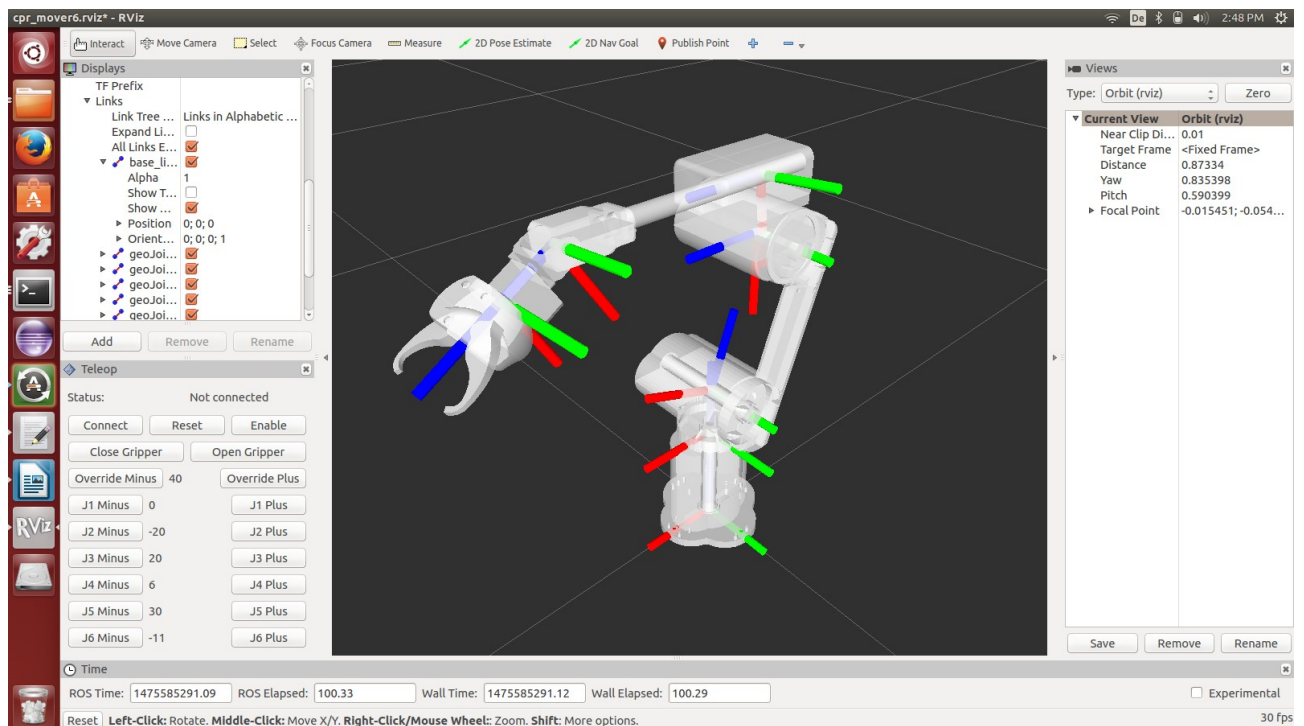
When the adapter is recognized by the OS the red LED on the adapter is on. When the adapter is connected by the software, it blinks slowly. When data is transmitted it blinks faster.

### 3. Start

- Start `roscore`
- Open a terminal and `cd` into the plugin directory: `cd ~/ros_workspace/cpr_rviz_plugin/`
- Start Rviz with the according launch file: `roslaunch cpr_mover4.launch`  
or `roslaunch cpr_mover6.launch`
- The CPR plugin should be loaded, otherwise load with the menu entry.
- Open a second terminal and `cd` into the `cpr_mover` directory: `cd ~/catkin_ws/src/cpr_mover`
- Start the node: `roslaunch cpr_mover cpr_mover`  
It is important to first start Rviz, because the launch file sets the `robot_type` parameter to choose between Mover4 and Mover6, `cpr_mover` uses this parameter. If RViz is not used it can be set in another way to the parameter server.
- If the package does not start: `source ./devel/setup.bash`

Now move the simulated robot. If this on moves connect the real robot:

- Press “Connect” in the RViz plugin. The status changes from “not connected” to another value
- Press “Reset”: This button loads the hardware joint status, the 3D graphics adapts. Also the status changes
- Press “Enable”: Not the status changes to “0x00” or “No Error” and the robot can be moved now.



## 4. Robot Geometries

For the Mover6 detailed CAD files in .obj format are provided. We also provide simplified .obj files for collision testing. These files are convex and with a low polygon count to allow fast collision computation. But of course the precision is not as in the original files. If you require precise collision testing please have a look at the files and in case use the graphics files also for collision testing.

The Mover4 files are currently based on geometry primitives, the update to CAD files will be done.

## 5. Interface Specification

Publishing Information takes place in `cpr_mover::CommunicationROS()` within the robot cycle time (standard: 20 Hz).

## 1 JointState Publisher

Type: `sensor_msgs::JointState`  
 Name: `/joint_states`

Provides, depending on the robot, 4 or 6 joint values + 2 gripper joint values of the robot in radian. The values are setpoint values, not the hardware values. Joint names are Joint0 to Joint5 and Gripper1, Gripper2.

The gripper is not commanded as servo joint, but using digital out by commands, see below.

Output from rostopic for Mover4:

```
header:
  seq: 2865
  stamp:
    secs: 1478854058
    nsecs: 53704958
  frame_id: "
name: ['Joint0', 'Joint1', 'Joint2', 'Joint3', 'Gripper1', 'Gripper2']
position: [-0.15438211956829492, -0.2922569486684799, 2.2388260246310763, -0.40591830430041415,
0.0, 0.0]
velocity: []
effort: []
```

## 2 Error Code Publisher

Type: `std_msgs::String`  
 Name: `/CPRMoverErrorCodes`

Provides a string with the current status of the robot arms hardware joints, the error codes.

## 3 Joint Velocity Subscriber

Type: `sensor_msgs::JointState`  
 Name: `/CPRMoverJointVel`

When there are no points to replay from the actionServer, the robot reacts to the jog values in these messages. The values in `msg->velocities[]` are percent values with respect to the `maxJointVelocity` defined in the source code. The allowed range is `[-100.0 .. 100.0]`.

## 4 Commands Subscriber

Type: `std_msgs::String`  
 Name: `/CPRMoverCommands`

The Mover reacts to commands received with these messages. Commands are:

- Connect
- Reset
- Enable

- GripperOpen
- GripperClose
- Override ppp where ppp is the percent value of the override (integer)

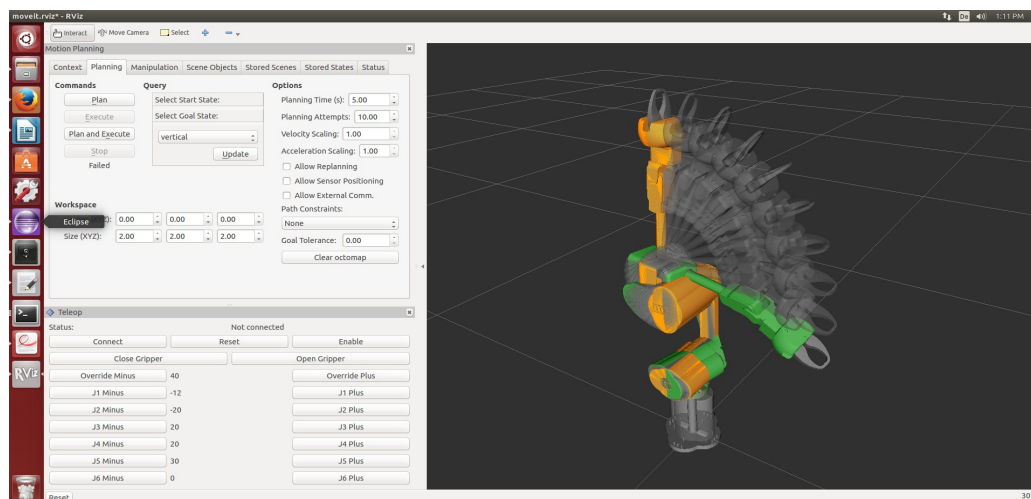
## 5 TrajectoryActionServer

Type: `actionlib::SimpleActionServer<control_msgs::FollowJointTrajectoryAction>`  
 Name: `cpr_mover/follow_joint_trajectory`

## 6 GripperCommandActionServer

Type: `actionlib::SimpleActionServer<control_msgs::GripperCommandAction>`  
 Name: `cpr_mover/gripper_command`

## 6. MoveIt Examples



The packages `mover4_moveit_config` and `mover6_moveit_config` contain simple example configurations. The robot follows the planned trajectory in simulation and reality.

Currently we get an error when starting also `cpr_mover` (the hardware interface) from within the `demo.launch` file. For this reason it is necessary to start both:

- \* Start MoveIt with: `roslaunch mover6_moveit_config demo.launch`
- \* Start `cpr_mover` with: `roslaunch cpr_mover cpr_mover`

It is important that before starting `cpr_mover` the type of robot is set:

```
<param name="robot_type" value="mover6"/>
```

This is done in the `demo.launch` file. `cpr_mover` sets the contents of the topics according to this parameter to 4 or 6 joints.

Attention: `cpr_mover` should be started directly after `moveit` so that it is running when `moveit` searches for the controller!

## 7. Trouble Shooting

- Slow, interrupted motions of the robot: Check if there are two TeleopPanels active in RViz. If this is the case delete both and load one again.
- No connection between cpr\_mover and Rviz: try to restart roscore and all nodes
- If there is a connection to the robot (e.g. you can open and close the gripper) but you cannot move the robot try if J5 might be above / below  $90/-90^\circ$ . If it is so move J5 into a position inside  $-90..90^\circ$ . Please do not use force, but remove power.