

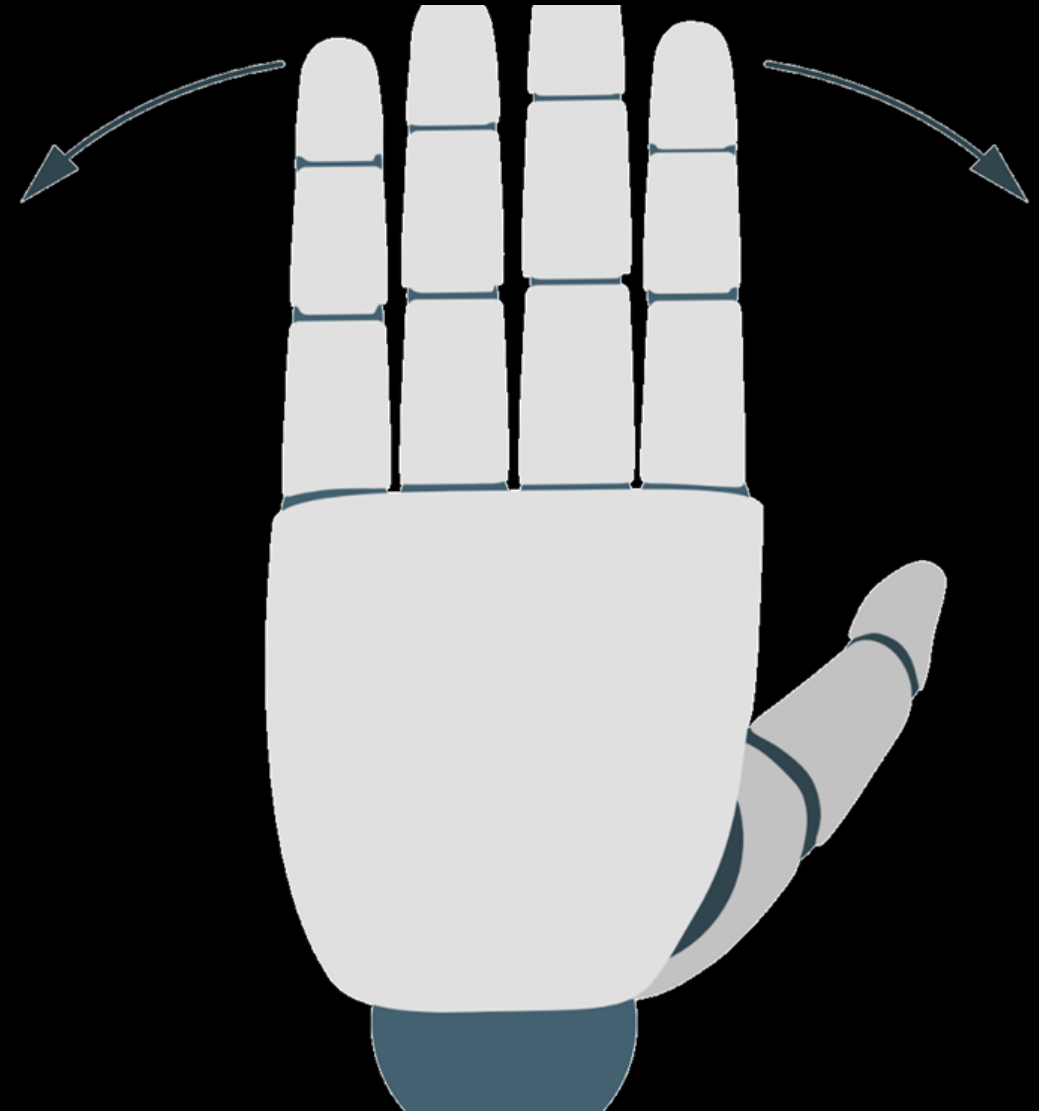


# Workshop Unit 6

Interfacing & Controlling your  
Robotic Hand

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# Overview



1. Required Materials
2. Structure of the Code Framework
3. Setup and running the example code

# Required Material



## Dynamixel Motors

Each motor must have a unique ID. See the guide for how to change the Dynamixel IDs.



## Dynamixel Equipment

- U2D2 w/ USB cable
- U2D2 Power Hub Board
- 12V Power Supply



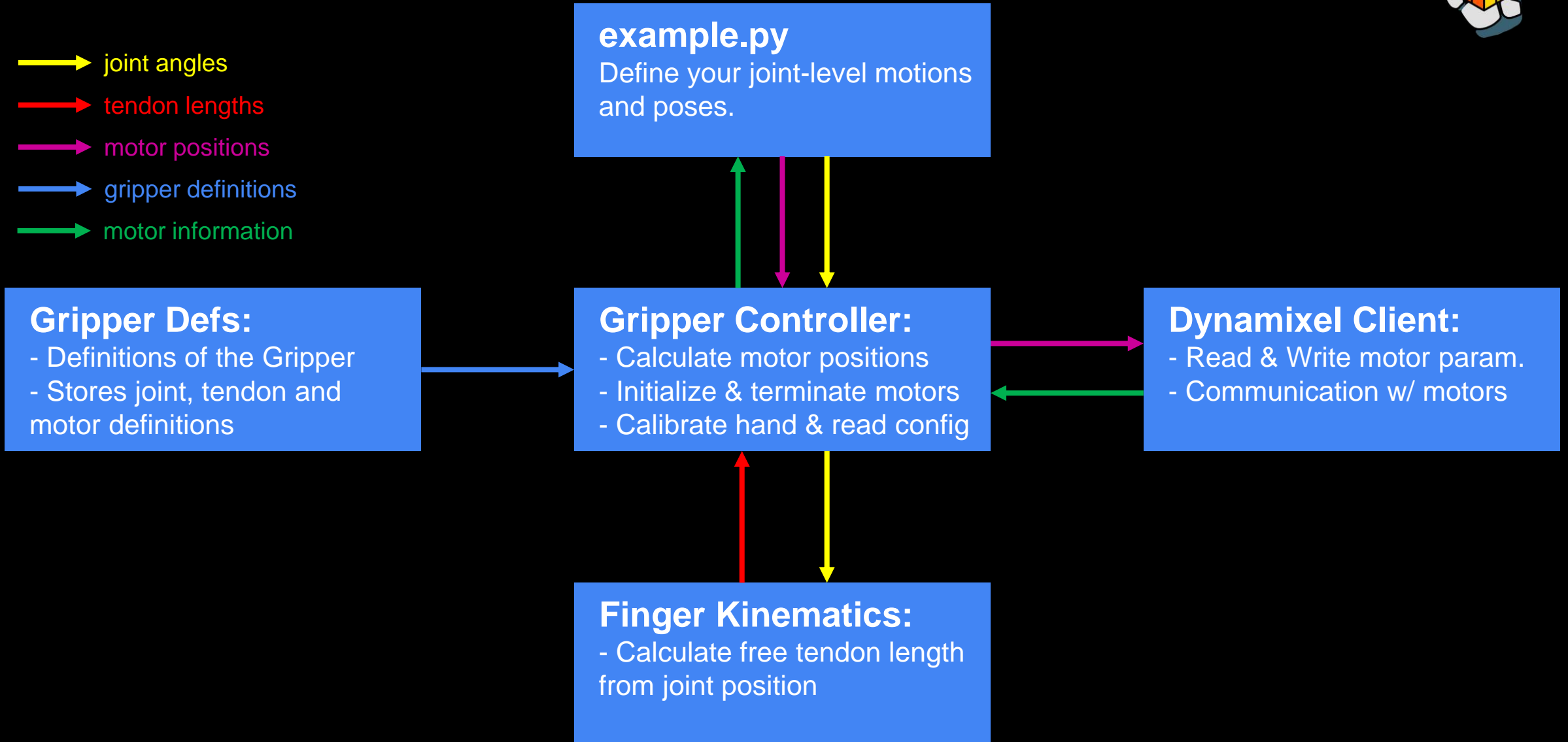
## Your own Computer

- Linux operating system
- *Python* installed
- *Dynamixel-SDK* installed



# Code Framework

- joint angles
- tendon lengths
- motor positions
- gripper definitions
- motor information





## Setup and running the example code

- Setup the Dynamixel motors
  - Set unique IDs for each motor
  - Set baudrate to 3 Mbps
- Run the example code
  - Run *example.py* and check if everything works
- Adjust the framework to your application
  - Implement your kinematics

