SDK 培训简要

一、SDK 使用培训：

1. 机器人安装

2. 机器人硬件结构、基础操作介绍

3. ROS 系统配置与机器人通讯

4. 官方例程序演示

5. GAZEBO、MOVEit、Rviz 安装及展示

6. Kinect 人机跟随演示（需客户自备 Kinect，仅 Baxter）

7. 维护、安全警告信息、常见故障讲解排除

附 1：Baxter 例程清单：

Running Example Research SDK Programs

Learn how to start your environment and run any of the SDK Examples below:

- Display Image Example
- Gripper Example
- Gripper Cuff Control Example
- Head Movement Example
- (New!) Head Action Client Example
- IK Service Example
- Input Output Example
- Joint Position Example
- Joint Torque Springs Example
- Joint Trajectory Playback Example
- Puppet Example
- Wobbler Example
- Simple Joint Trajectory Example

附 2：Sawyer 例程清单：

MOVEMENT

Gripper Example - Joystick and Keyboard control for the gripper.

Gripper Cuff Control Example - Simple cuff-interaction control with Zero-G mode.

Head Movement Example - Simple demo moving the head.

Inverse Kinematics Service Example - Basic use of Inverse Kinematics solver service.

Joint Position Example - Joystick, keyboard control for Sawyer's arm.

Joint Position Waypoint Example - Hand-over-hand teach and recording a number of joint position waypoints. These waypoints will then be played back.

Joint Torque Springs Example - Joint torque control example applying virtual spring torques.

Joint Trajectory Playback Example - Trajectory playback using the joint trajectory interface.

INTERACTION CONTROL

Set Interaction Options Example - Example script for setting interaction control parameters in the current configuration.

INPUT AND OUTPUT

Camera Image Display Example - Example tool for viewing cameras feed of Sawyer robot on development machine.

Head Display Image Example - Example tool for displaying image files (png, jpeg) on the Head Screen.

Lights Blinking Example - Flash the lights on the digital outputs.