

Ross Kasal

Guide for drawing

For all terminals:

```
source ~/ros_ws/devel/setup.bash
baxter_master
cd
cd ros_ws
catkin_make
```

Terminal 1:

```
roslaunch baxter_tools enable_robot.py -e
roslaunch baxter_tools tuck_arms.py -t
roslaunch baxter_tools tuck_arms.py -u
```

Terminal 2:

```
roslaunch baxter_launch_files baxter_playfile_nodes.launch
```

Terminal 3:

```
roslaunch baxter_trajectory_streamer rt_arm_as
```

Terminal 4:

```
user@atlas8:~/ros_ws/src/EECS-651-Testing/Part_5/baxter/baxter_playfile_nodes$ roslaunch
baxter_playfile_nodes baxter_playback baxter_r_arm_traj.jsp
```

Note: Look at the specific directory you have to go to this directory to run the jsp

Terminal 5:

```
roslaunch baxter_playfile_nodes baxter_recorder
```