RightHand Labs

ReFlex Documentation

Contact

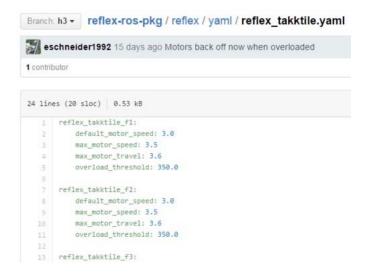
## 8) Getting under the hood (Takktile)

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There are a couple parameters that you can change to affect the behavior of the hand. This tutorial will tell you where to find them and what they are.

## reflex\_takktile.yaml

Inside the <u>yaml folder in the reflex package</u> you'll find the reflex\_takktile.yaml file. Inside of it there are a number of things that can changed to affect the hand behavior.



- default\_motor\_speed: This is the default speed the motors travel at when given a position command.
- max\_motor\_speed: When commanded to a higher speed than this, the code will clamp the command down to
  this max speed. The motors can't physically travel much faster than this.
- max\_motor\_travel: Maximum position in radians that the motors can be commanded to.
- overload threshold: This is the motor load at which the hand interrupts a command and loosens. If you need
  the hand to grip harder this can be adjusted, but be careful not to overheat the motor or physically damage
  the fingers when the motors grip with more force.

## reflex driver.launch

Inside of the <u>launch folder in the reflex\_driver package</u> you'll find the reflex\_driver.launch file. Inside is the default sensor threshold, which can be adjusted so that the sensors start off with a different default contact threshold.



## **Bagfiles**

Finally, it might be of interest that each time the hand code is run it saves the hand data in a rosbag file. Inside of the reflex package the latest run is stored in the bagfiles folder. The data is overwritten each time the hand is run, so if you want to save certain runs you should rename or otherwise move them.

To read more about ROS bagfiles, check out the ROS documentation. They can be used to save data and play it

back later.

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