

bot\_common\_ros.ur10  
\_driver.UR10Driver.on  
\_shutdown

```
graph LR; A[bot_common_ros.ur10_driver.UR10Driver.on_shutdown] --> B[bot_common_ros.ur10_driver.UR10Driver.close_robot]; A --> C[bot_common_ros.ArmServer.ArmServer.STOP];
```

The diagram illustrates a sequence of operations triggered by a shutdown event. A central box on the left, representing the `on_shutdown` function of the `UR10Driver`, has two outgoing arrows. The top arrow points to a box representing the `close_robot` method of the `UR10Driver`. The bottom arrow points to a box representing the `STOP` command of the `ArmServer`.

bot\_common\_ros.ur10  
\_driver.UR10Driver.close\_robot

bot\_common\_ros.ArmServer.  
ArmServer.STOP