

# URDF model controls real robot arm

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Note: This course is based on the [Robot Arm URDF Model] course. You need to start the URDF model of the robot arm, then run the program to drive the real robot arm, and then control the real robot arm through the URDF model.

## 2.1. Control the real machine

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### Simulation start

Reopen a terminal.

- Enter the following command to start the program

```
ros2 launch jetcobot_description display.launch.py
```

### 3. Drive the real machine

Reopen a terminal.

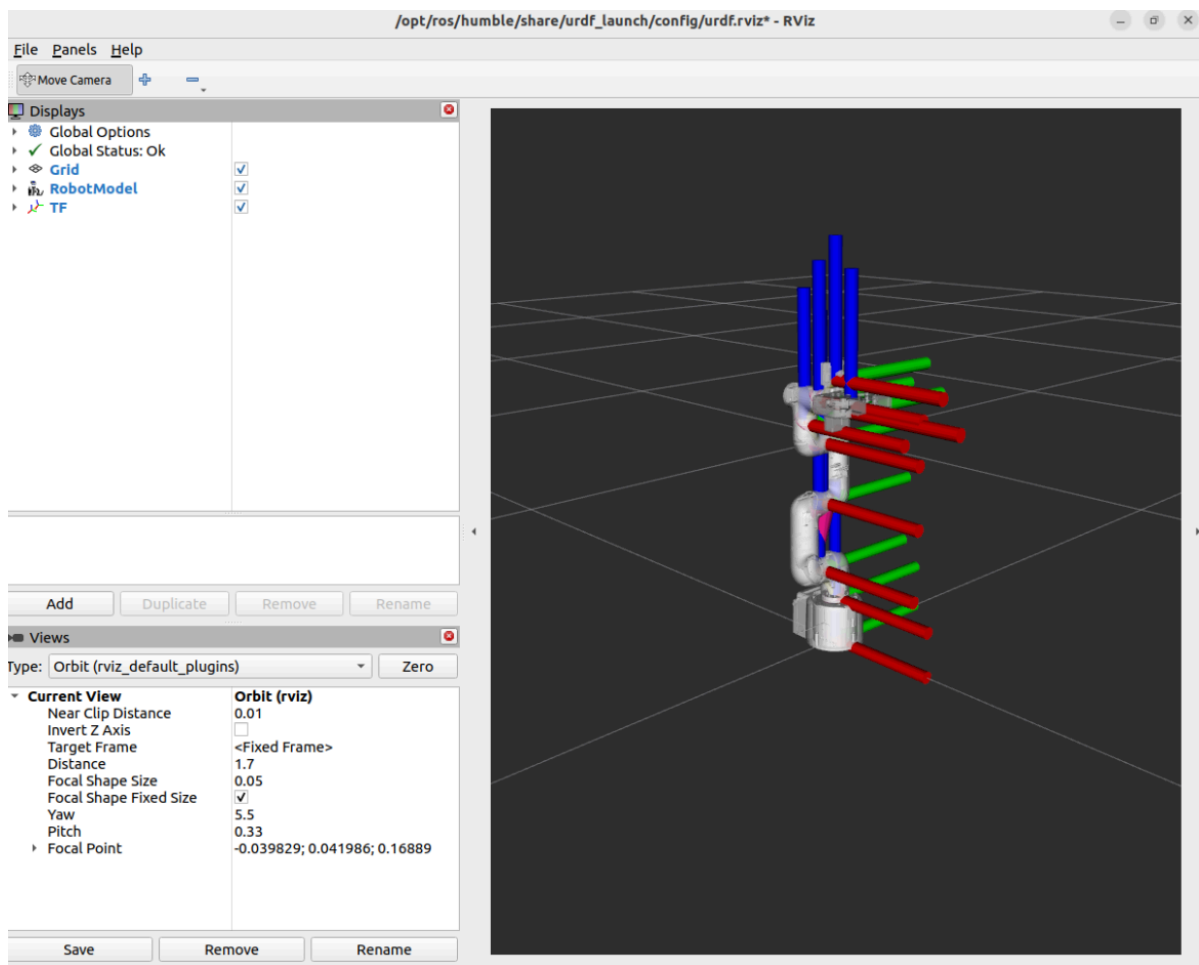
- Enter the following command to start the program

```
ros2 run jetcobot_driver sync_plan
```

**Note: After the program to drive the real machine is running, the robot arm will move with the simulation robot. Please be careful not to place other things around to avoid being hit by the robot arm.**

### 4. Verify the effect

At this time, in the robot arm URDF model,



At this time, controlling the joint simulator will control the real robot arm to move together,

