Control the robot arm posture

1. Important code explanation

Code path: ~/jetcobot_ws/src/jetcobot_ctrl/scripts/ctrl_poses.ipynb

Create a reset button to control the robot arm to restore the default posture.

```
def reset_joints():
mc.send_angles([0, 0, 0, 0, 0, -45], 50)
mc.set_gripper_value(100, 50)
```

Create 10 postures for the robot arm.

```
def ctrl_poses(id):
    if id == 1:
        angles = [-2.72, 49.39, -128.67, 76.72, 3.16, -44.2]
        mc.send_angles(angles, g_speed)
    elif id == 2:
        angles = [-84.63, -85.78, -0.61, 93.07, 86.22, -44.2]
        mc.send_angles(angles, g_speed)
    elif id == 3:
        angles = [93.69, -85.78, -0.61, 85.78, -86.13, -44.29]
        mc.send_angles(angles, g_speed)
    elif id == 4:
        angles = [0.26, -40.42, -50.62, 92.98, -0.79, -44.2]
        mc.send_angles(angles, g_speed)
    elif id == 5:
        angles = [0.35, 63.1, -143.26, 73.82, 10.81, -44.73]
        mc.send_angles(angles, g_speed)
    elif id == 6:
        angles = [0, 15, -135, 123, 25, -45]
        mc.send_angles(angles, g_speed)
    elif id == 7:
        angles = [0.43, -0.96, -3.69, 88.76, 10.81, -47.63]
        mc.send_angles(angles, g_speed)
    elif id == 8:
        angles = [97.55, 59.85, -130.25, 70.22, -88.5, -42.01]
        mc.send_angles(angles, g_speed)
    elif id == 9:
        angles = [0.43, 89, -93.95, -36.73, 10.45, -46.23]
        mc.send_angles(angles, g_speed)
    elif id == 10:
        angles = [108.19, -92.1, 125.85, -79.71, 9.74, -43.95]
        mc.send_angles(angles, g_speed)
```

2. Run the program

Click the Run the entire program button on the jupyterlab toolbar, and then pull it to the bottom.

You can see that multiple buttons are displayed. The robotic arm has ten preset postures. You can click the corresponding button to make the robotic arm move to the corresponding posture.