Robot arm URDF model

1.1. Introduction

URDF model stands for Unified Robot Description Format, which is a file used to describe various attributes of the robot, such as appearance and performance. It can not only clearly describe the model of the robot itself, but also describe the external environment of the robot, such as a table, which can also be counted as a model. The default factory system has configured the URDF model of the jetcobot robot arm.

1.2. Start the URDF model

Simulation start

Reopen a terminal.

- Enter the following command to start the program

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

1.3. Experimental phenomenon

You can see that the system pops up the RVIZ software window and loads the URDF model of the Jetcobot robot arm.

Note: The commands in this course only control the robot arm in the URDF model, and will not control the real robot arm.
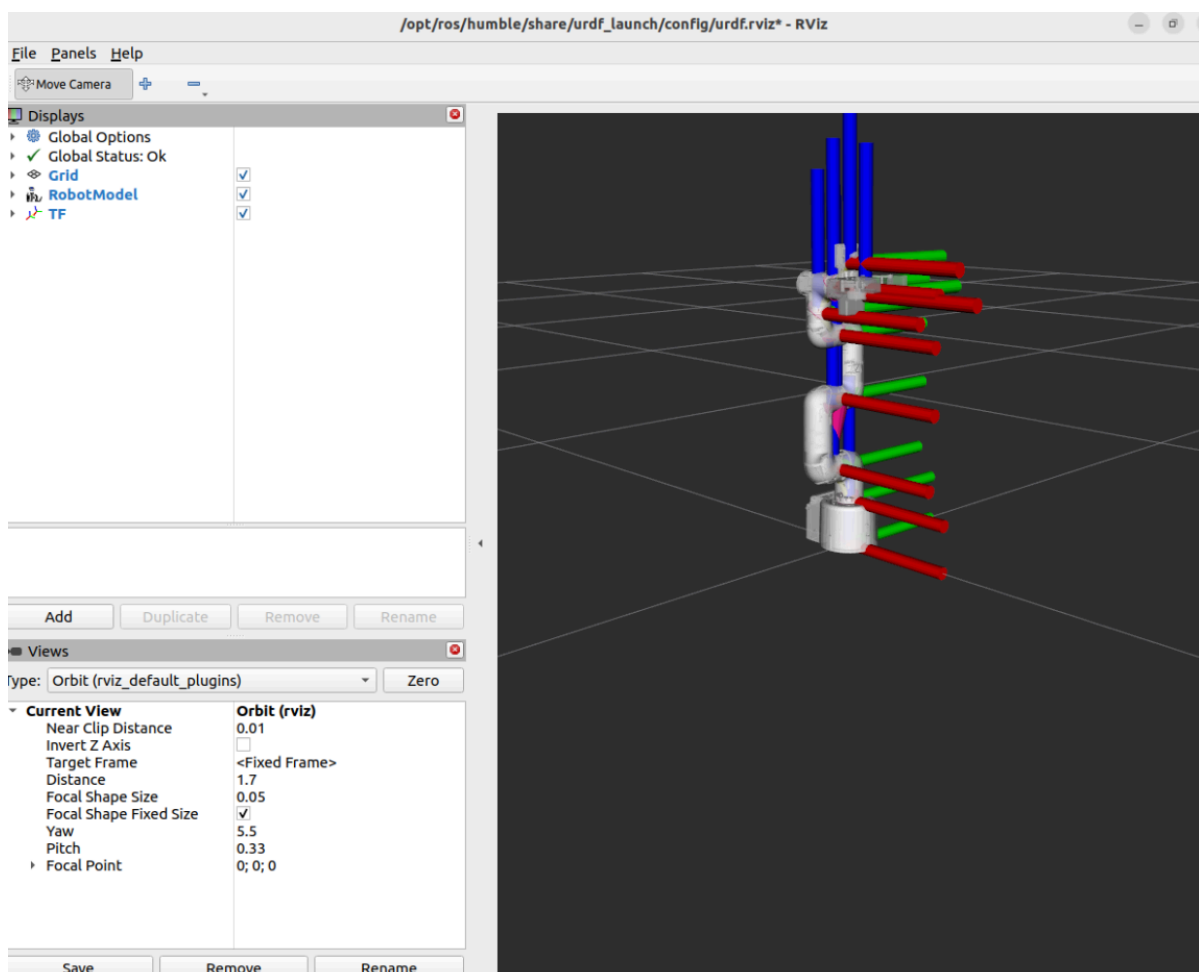
Close case: [ctrl+c] to close, if it fails, press [ctrl+z].

Joint simulator: Control each joint of the robot arm by adjusting the slider

Joint State Publisher — ☐ ✕

Randomize

Center

1_Joint   0.00

2_Joint   0.00

3_Joint   0.00

4_Joint   0.00

5_Joint   0.00

6_Joint   0.00