

Gripper control

set_gripper_value

description:set gripper angle

parameters:

1.gripper angle

2.the speed at which the gripper executes running

returned value:none

set_gripper_state

description:set the opening and closing states of the gripper

parameters:

1.gripper states: 0: open; 1: close

2.the speed at which the gripper executes running

returned value:none