

Andrew Tarnoff

Mobile Robot Programming Problem Set #6

CODE LINK:

https://github.com/art81/EECS373/tree/master/MobileRobotics/PS6_baxter_variations

Changes Made to enable the control of baxter arms:

In order to gain control over the baxter arms it did not actually require any changes to the robot urdf, or xacro files. Instead, the baxter_tools package already includes a function that enables the robot to be controlled. To run this function just type “roslaunch baxter_tools enable_robot.py -e” into the command line and now you have control over the arms. The baxter_tools package also provides a python script that will command a joint trajectory to the arms and to run that just type “roslaunch baxter_tools tuck_arms.py -u” into the command line to test if you actually have control over robot joint positions. In my video I also show that after running the “enable_robot” command you can command joint positions through the command line using “rostopic pub” which also means it would be easy to write our own node that commands joint trajectories.