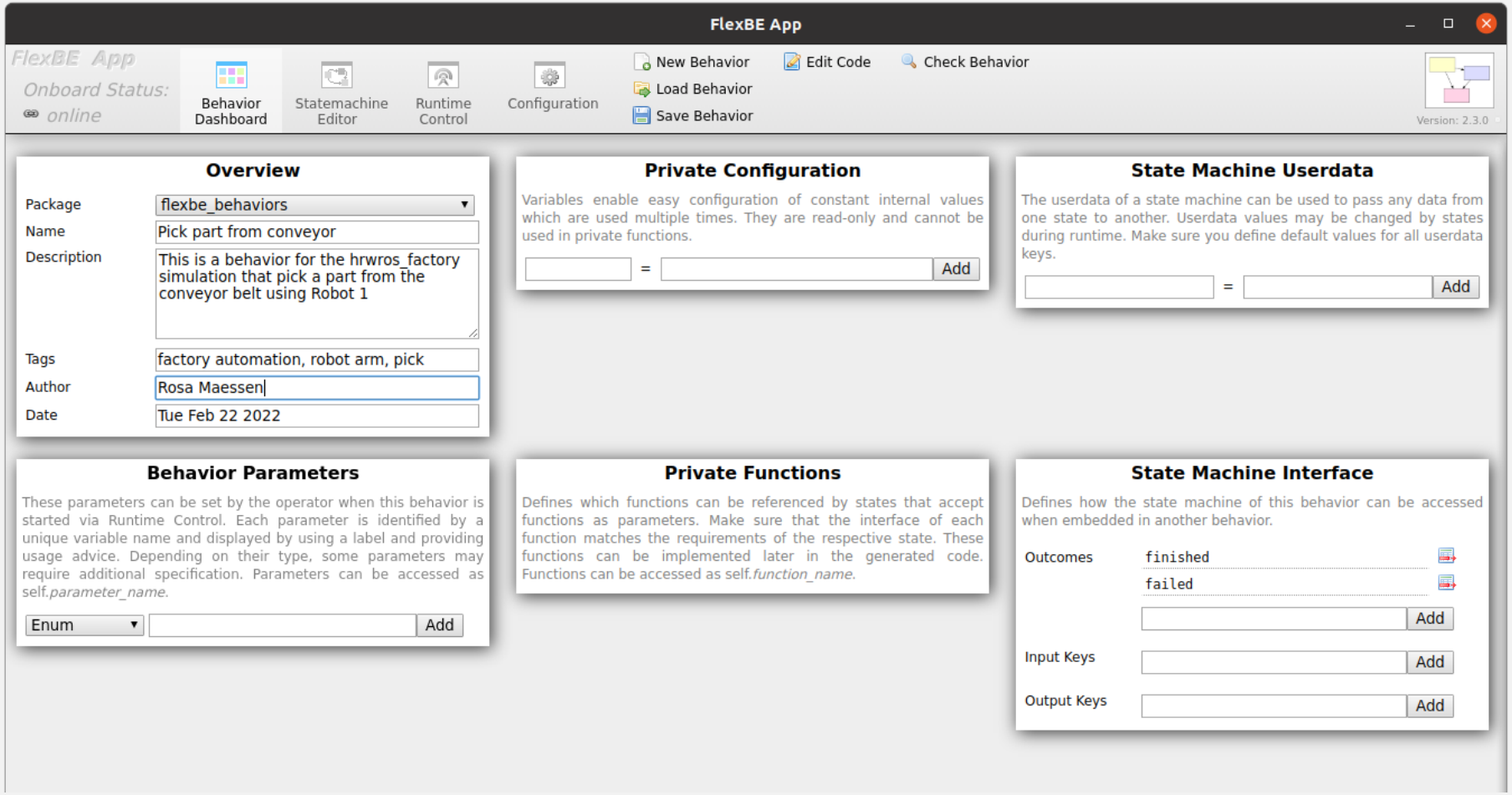
6.3.2

Configure a behavior

Carlos Hernandez

Behavior configuration

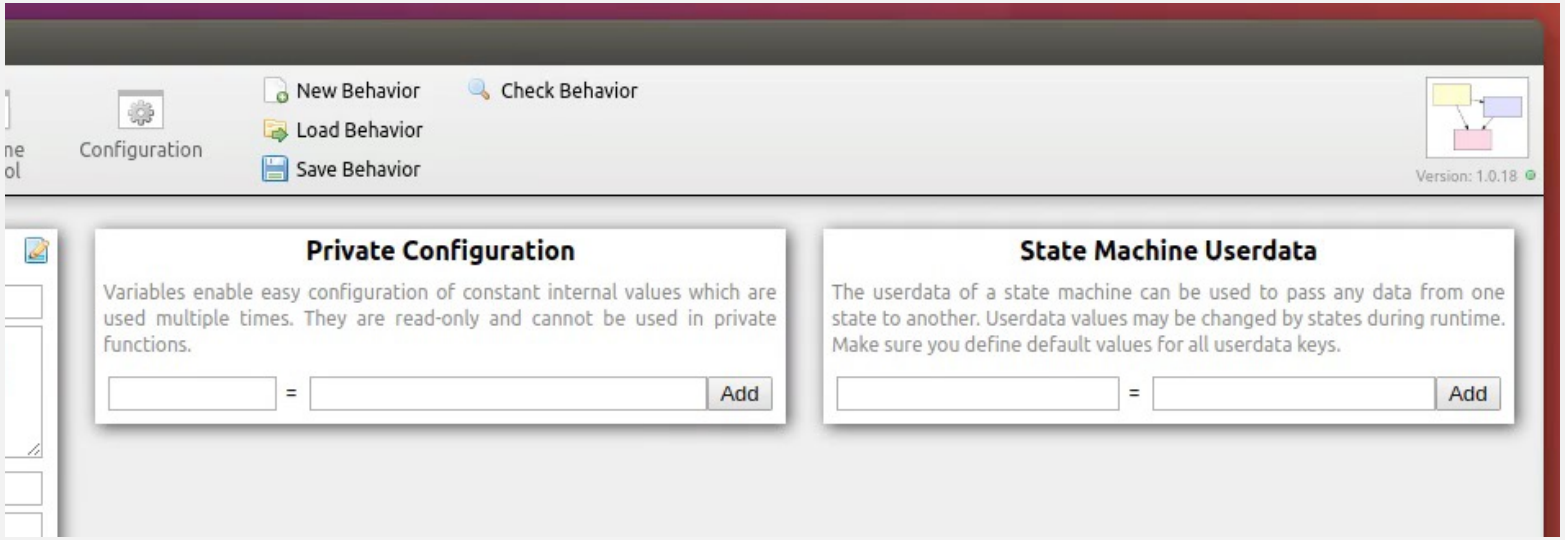


Behavior constants

- **Constant** values used in our behavior.
- FlexBE variables defined in **Private Configuration.**

hrwros.srdf

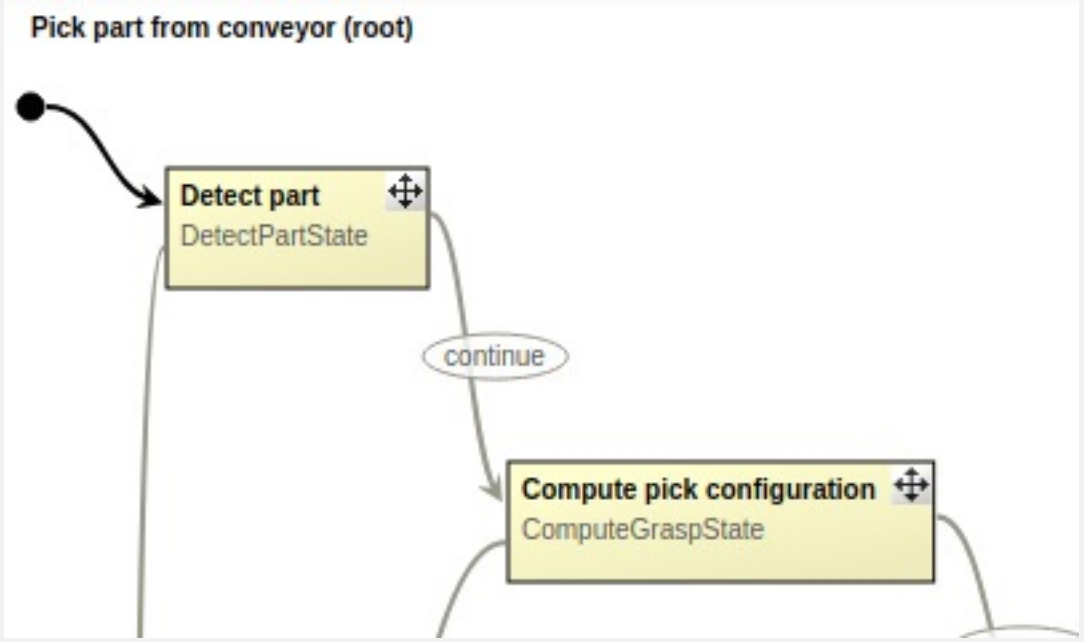
```
12        <group name="robot1">
13            <chain base_link="robot1_base_link" tip_link="v
14        </group>
```



Userdata

- Data can flow between states and **change at runtime**.
- **Userdata** variables in FlexBE
- Default values required.

- pose of the part to pick
- robot configuration for picking

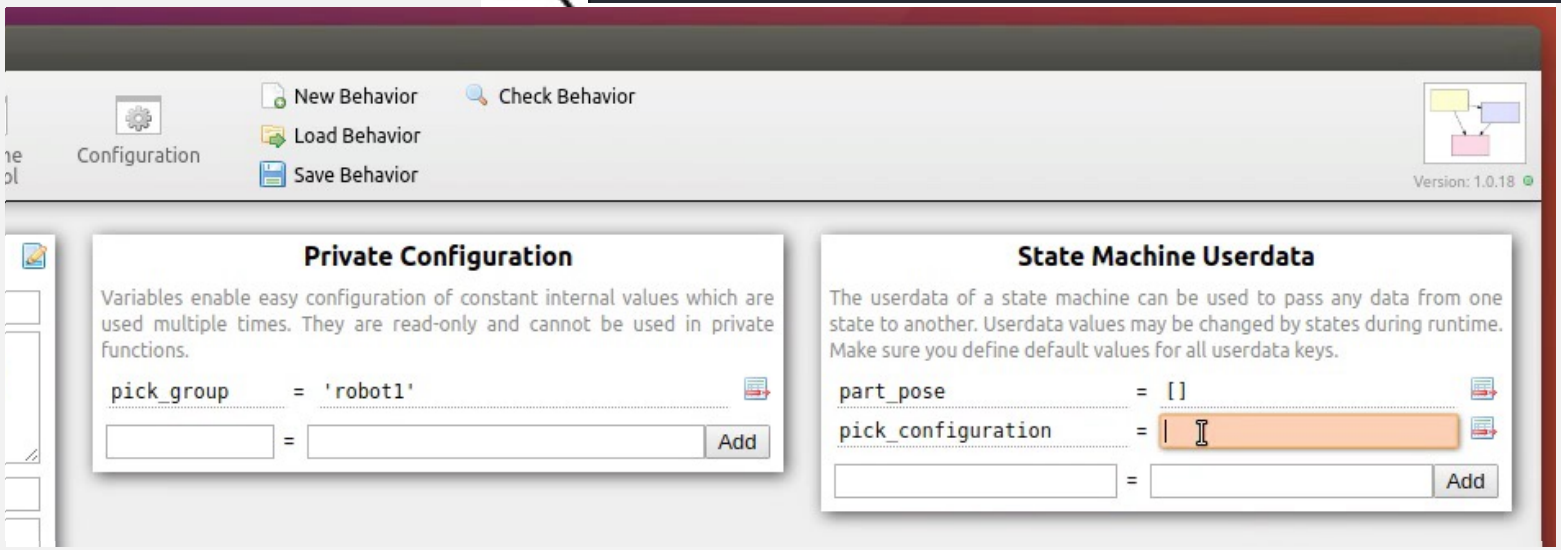


Userdata

- Data can flow between states and **change at runtime**.
- **Userdata** variables in FlexBE
- Default values required.

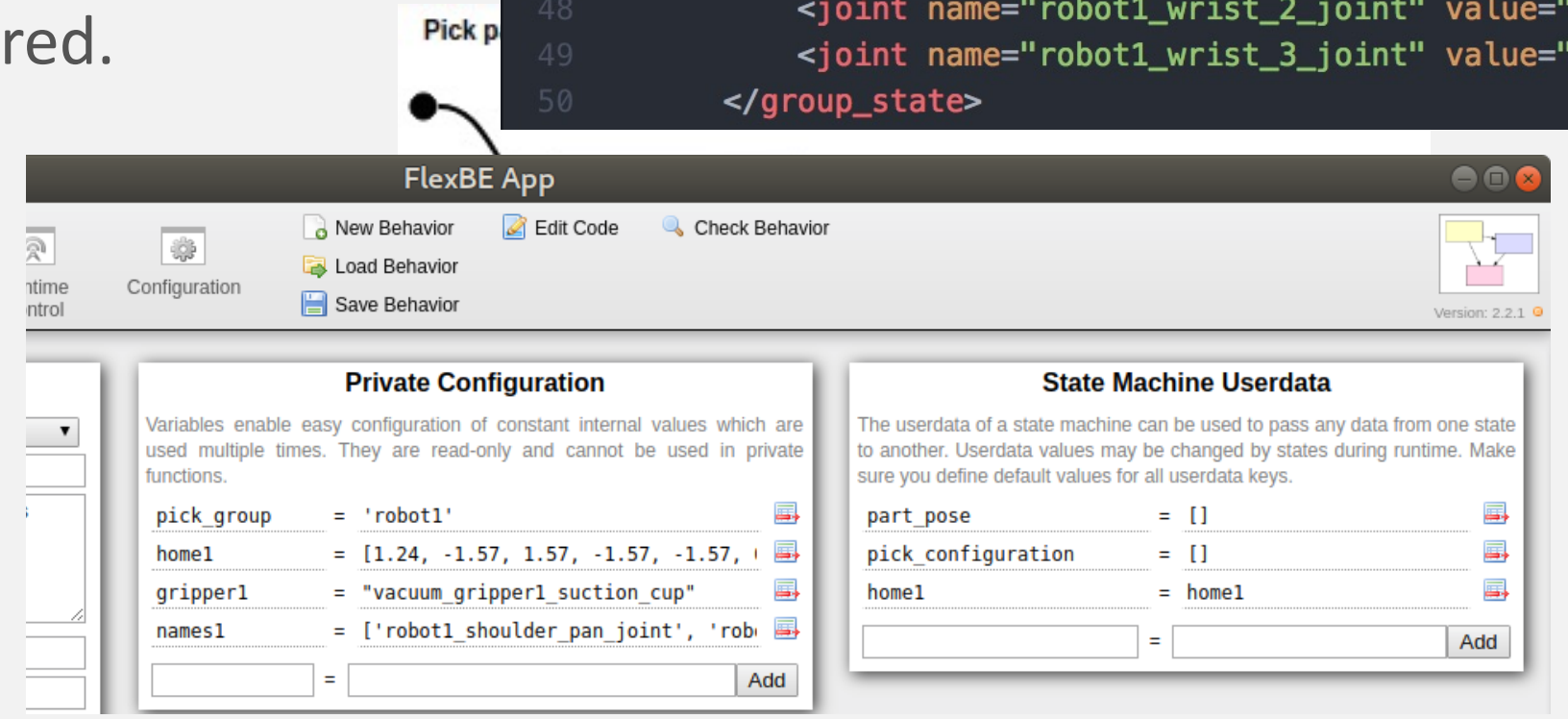
hrwros.srdf

```
43        <group_state name="r1home" group="robot1">
44            <joint name="robot1_elbow_joint" value="1.5
45            <joint name="robot1_shoulder_lift_joint" va
46            <joint name="robot1_shoulder_pan_joint" valu
47            <joint name="robot1_wrist_1_joint" value="-
48            <joint name="robot1_wrist_2_joint" value="-
49            <joint name="robot1_wrist_3_joint" value="0
50        </group_state>
```



Userdata

- Data can flow between states and **change at runtime**.
- **Userdata** variables in FlexBE
- Default values required.

hrwros.srdf

```
43        <group_state name="r1home" group="robot1">
44            <joint name="robot1_elbow_joint" value="1.5
45            <joint name="robot1_shoulder_lift_joint" va
46            <joint name="robot1_shoulder_pan_joint" valu
47            <joint name="robot1_wrist_1_joint" value="-
48            <joint name="robot1_wrist_2_joint" value="-
49            <joint name="robot1_wrist_3_joint" value="0
50        </group_state>
```