Baxter Robot Startup Procedure

Execute the following steps to startup the robot correctly:

1. Startup the desktop and login.
2. Make sure the Ethernet cable from the router is plugged into the robot. Then select the network icon in the top corner of the screen and connect to the *baxter* network.
3. Turn the Baxter robot on and wait for the robot to boot up completely (solid green light at the top of the robot and rethink robotics logo on robot screen).
4. Open a new terminal window.
5. Type *ping 192.168.0.1* to check the connection to the router, when confirmed press Control + C to stop.
6. Type *ping 011311P0016.local* to check the connection to the Baxter robot, when confirmed press Control + C to stop.
7. Type *cd ~/ros_ws_v6/* to open the main directory used for Baxter operations.
8. Type *source devel/setup.bash*
9. Type *./baxter.sh* to open the shell that communicates with the Baxter robot.
10. Type *rosrun baxter_tools enable_robot.py -s* to get the current state of the Baxter Robot. The output should look like:
    enabled: False
    stopped: False
    error: False
    estop button: 0
    estop source: 0
    If you see *estop button: 1* it means the emergency stop button has been pressed, twist the button then type *rosrun baxter_tools enable_robot.py –r* to reset it.
    Try *rosrun baxter_tools enable_robot.py -s* again to see if the desired output is now displayed.
11. Type *rosrun baxter_tools enable_robot.py –e* to enable the robot.
12. Type *rosrun baxter_tools tuck_arms.py –u* to untuck the arms into their home position. Once this operation has been completed the Baxter robot is ready to run.