

## Baxter Robot Shut Down Procedure

Execute the following steps to shut down the robot correctly:

1. Type *roslaunch baxter\_tools tuck\_arms.py -t* to tuck the arms into their storage position.
2. Type *roslaunch baxter\_tools enable\_robot.py -d* to disable the Baxter robot.
3. Type *roslaunch 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 *roslaunch baxter\_tools enable\_robot.py -r* to reset it.

Try *roslaunch baxter\_tools enable\_robot.py -s* again to see if the desired output is now displayed.

4. Close the terminal window that the Baxter robot was being used with.
5. Turn off the Baxter robot, the robot is completely powered off when the fans stop and the lights turn off.