

Steps For Using Physical Baxter

Boot Up

1. Ensure Ethernet is unplugged from Baxter
2. Reboot Laptop
3. Turn Baxter on (white push button on back)
4. Wait for following
 - a. Green LED ring lights up on Baxter's head
 - b. Ultrasonic sensors turn on (listen for them)
 - c. No more load screen on face screen
5. Plug Ethernet into Baxter
6. Run “cd baxter_ws → ./bax.sh → source devel/setup.bash”
7. Run “rostopic list” and make sure all of baxter's topics show up
8. Good to run your code

Power Down

1. End your code (ctrl C)
2. Run “roslaunch baxter_tools tuck_arms.py -t”
3. Run “roslaunch baxter_tools enable_robot.py -d”
4. Turn Baxter off (press white push button on back DO NOT HOLD)