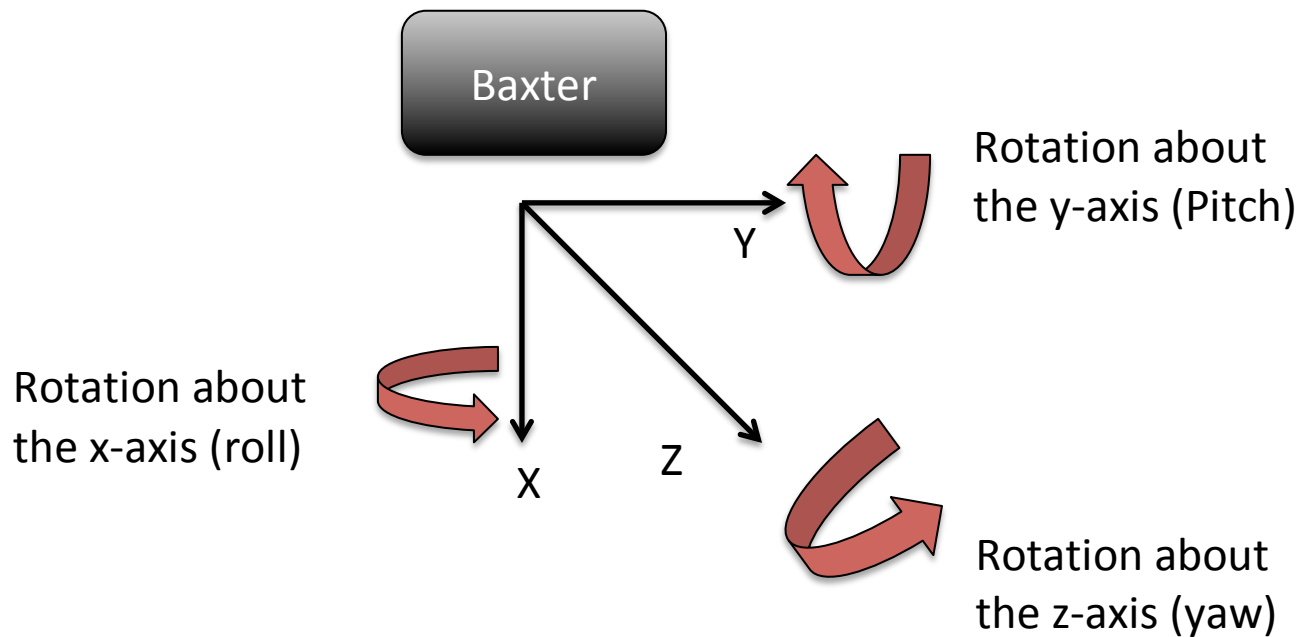


Baxter Gripper Movement and Orientation Coordinate system



The coordinate system for the Baxter robot is outlined in the diagram above, the origin point is within the center of Baxter's base approximately level with the point where the base is bolted to the stand.

For the orientation of the gripper the coordinates are given as 3 angles however you will need to use the Euler to Quaternion conversion subroutine to convert these to the Quaternion coordinate system that Baxter uses (see READ ME Nodes document in nodes file). The first of these angles is anticlockwise rotation about the y-axis (sometimes known as pitch), the second is anticlockwise rotation about the x-axis (sometimes known as roll) and the third is anticlockwise rotation about the z-axis (sometimes known as yaw). All of these are from the perspective away from Baxter i.e. with the x-axis pointing away from you and looking in the same direction as Baxter. The orientation (0,0,0) is the gripper facing towards the floor with the camera on the wrist the opposite side of the gripper than Baxter.