

Baxter Robot Shut Down Procedure

Execute the following steps to shut down the robot correctly:

1. Type *'rosrun baxter_tools tuck_arms.py -t'* to tuck the arms into their storage position.
2. Once the arms have been tucked and finished moving, type *'rosrun baxter_tools enable_robot.py -d'* to disable the Baxter robot.
3. Type *'rosrun baxter_tools enable_robot.py -s'* to get the current state of the Baxter Robot and make sure it has been disabled correctly. The output should look like:

enabled: False

stopped: False

error: False

estop button: 0

estop source: 0

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.