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# **RVL UR-Robotiq Integrated Driver Documentation**

*Release 0.0.1-alpha*

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RVL UR-Robotiq Integrated Driver is a wrapper for the existing ROS services and topics provided by Universal Robots (UR) ROS Driver with additional support for Robotiq gripper (currently support 2F) directly attached to the UR tool port.

This driver also provides additional function for actuating the gripper in various modes (grasp on open/close, specific jaw gap, etc.) as well as integrating MoveIt! motion planning that tracks the entire setup, UR and Robotiq gripper.

At the time of writing, the driver is working on our setup on both Windows 10 (Version 10.0.19044 Build 19044) and Ubuntu 20.04.



## QUICKSTART

### 1.1 Universal Robot Setup

#### 1.1.1 Setup RS485 URCap and socat

Follow the [step by step instructions](#) provided by Universal Robots to allow tool communication via a socket on port 54321.

The control box file system can be accessed via `ssh root@[ROBOT-IP]` with the default password `easybot`. You should see the internal UR prompt, something along the line of

```
Universal Robots A/S Linux image
```

```
Production image
```

```
root@ur-[serial]:~#
```

`socat` can be installed from there from source or using a package manager. You may want to use the attached `socat-robotiq-gripper.service` so `socat` starts every time on system power on.

To setup the service file, just put it in `/etc/systemd/system/` and run

```
$ sudo systemctl enable socat-robotiq-gripper.service
```

which will start the `socat` service on boot.

### 1.2 Docker Environment Setup

#### 1.2.1 Installing Docker

```
$ sudo apt-get install docker.io
```

or follow Docker on WSL 2 backend installation guide at [Get Docker](#).

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**Note:** If you are on Linux, be sure to follow [Docker Post-Installation Steps](#).

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## 1.2.2 Clone the Repository

```
$ git clone https://github.com/robotic-vision-lab/UR-Robotiq-Integrated-Driver
```

## 1.2.3 Build or Pull the Docker Image

You can build the image using the Dockerfile already included in the repository

```
$ cd UR-Robotiq-Integrated-Driver/scripts
$ docker build -t rvl_driver -f name.dockerfile .
```

or you can pull it directly from Docker Hub with `docker pull mqt0029/rvl-ur-robotiq-driver:latest`. If you pulled from Docker Hub, be sure to retag your image to `rvl-ur-robotiq-driver:latest`

```
$ docker tag mqt0029/rvl-ur-robotiq-driver:latest rvl-ur-robotiq-driver:latest
```

or update the image name in the launch script accordingly.

## 1.2.4 Creating the ROS Container

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**Note:** Be sure to check your image name before running the script.

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The included `[windows_]launch_docker_container.sh` is a useful script in creating and accessing docker containers created from the built/pulled image. Simply run

```
$ sh launch_docker_container.sh
```

First run will create the container if it is not already existed. Subsequent run will attached the terminal to the docker container via `bash`. At this point, you should see the following prompt:

```
[...]
root ~/catkin_ws
>
```

## 1.3 Inside the container

With our specific setup of running UR5e and Robotiq 2F-85 gripper, we have customized the accompanying `xacro` (hence, also includes generated `urdf`) to match our specific machine description. You may want to modify the launch file to use the correct files for your setup.

While the base path is commonly `[...]/catkin_ws/src`, this is not always the case. Paths will be relative to where you place your ROS packages.



### 1.3.1 Robot Xacro and URDF

The included ROS package `rvt_robot_description` contains an example of our robot setup. The file `[...]/rvt_robot_description/xacro/rvt_ur5e.xacro` can be a good place to start and components should be fairly straightforward to swap in and move around.

### 1.3.2 Universal Robots Driver Bringup

The `ur_robot_driver` package launch file has been modified to work with the tool port gripper and our specific setup. You can use the launch file `[...]/rvt_ur_remote_dashboard/launch/rvt_ur5e_bringup.launch` as a reference, and modify it to fit your setup. The important section is highlighted below.

```
<arg name="robot_ip" default="192.168.1.147" doc="IP address by which ..."/>
<arg name="robot_description_file" default="$(find rvt_ur_remote_dashboard)/launch/load_
↳ rvt_ur5e.launch" doc="Robot description launch file."/>
<arg name="kinematics_config" default="$(find rvt_ur_remote_dashboard)/configs/ur5e_
↳ calibration.yaml" doc="Kinematics config file used ..."/>

<!-- always start the UR side socat -->
<arg name="use_tool_communication" default="true" doc="On e-Series robots tool_
↳ communication can be enabled with this argument"/>
```

**Warning:** Double check your calibration file is correct or [retrieve it accordingly](#).

**Warning:** Make sure your robot description is correct! This is crucial to generating your own URDF and SRDF that MoveIt! uses to plan all subsequent motion!

### 1.3.3 Building and Running ROS

A few aliases has been provided to quickly setup ROS dependencies and paths. `bash` will also automatically source `devel/setup.bash`.

```
$ run_rosdep
[...] installing dependencies

$ rebuild_catkin
[...] building catkin workspace

$ roslaunch <your_stuff>
```

## 1.4 Debugging

Since this driver is built inside a Docker container, the most common issue is networking. A good place to start is if all the ports (or network interface) is exposed properly, the robot IP is correct, and there is nothing interfering with ROS communications both ways. Otherwise, the host OS should not be a problem.

However, should any issues arise, please [open an issue on our GitHub repository](#).

## RVL UR-ROBOTIQ API

Due to how ROS structured Python source code and workspace setup, the module/package terminology usage might be confusing here.

### 2.1 Imports

```
from rvl_robotiq_controller.RobotiqController import Robotiq2FController
from rvl_ur_remote_dashboard.URRemoteDashboard import URRemoteDashboard
from rvl_ur_motion_planner.URMoveitCommander import URCommander
```

These are the primary modules and classes that covers most of the use case. The supporting functions might provide additional insights and is accessible as well.

`Robotiq2FController` is a wrapper to control Robotiq 2F grippers.

`URRemoteDashboard` is a wrapper for handling services and status monitoring as described on [ROS Interface page in UR Driver Repository](#).

`URCommander` is a wrapper for `MoveIt!` with some function built-in (pose goal, joint goal, etc.). Additional features are planned in future releases.

### 2.2 Modules Quick Access

These are links to quickly access modules mentioned under Import section. Otherwise, the full documentation of the entire driver is in the next section. Documentation will continue to be updated and covers more modules as the driver is being developed.

`rvl_robotiq_controller.RobotiqController.Robotiq2FController`

`rvl_ur_remote_dashboard.URRemoteDashboard.URRemoteDashboard`

`rvl_ur_motion_planner.URMoveitCommander.URCommander`

## 2.3 Full Modules Documentation

### 2.3.1 Gripper Control

rvl\_robotiq\_controller ROS Package

rvl\_robotiq\_controller package

Submodules

rvl\_robotiq\_controller.Robotiq2FSupport module

```
rvl_robotiq_controller.Robotiq2FSupport.generate_2f_status_from_binary(binary)
rvl_robotiq_controller.Robotiq2FSupport.generate_binary_command_from_2f_msg(message)
rvl_robotiq_controller.Robotiq2FSupport.raw_to_rad_2f140(raw)
rvl_robotiq_controller.Robotiq2FSupport.raw_to_rad_2f85(raw)
```

rvl\_robotiq\_controller.Robotiq3FSupport module

rvl\_robotiq\_controller.RobotiqController module

```
class rvl_robotiq_controller.RobotiqController.Robotiq2FController(stroke: int, default_force: int = 100, default_speed: int = 100, initialize: bool = False, startup_reset: bool = False, calibrate: bool = False, bypass_power: bool = False)
```

Bases: object

```
__init__(stroke: int, default_force: int = 100, default_speed: int = 100, initialize: bool = False, startup_reset: bool = False, calibrate: bool = False, bypass_power: bool = False) → None
Controller for basic Robotiq 2F Gripper operation.
```

#### Parameters

- **stroke** (*int*) – Stroke of the gripper. 2F grippers must use either 85mm or 140mm.
- **default\_force** (*int*, *optional*) – Default gripping force. Defaults to 100.
- **default\_speed** (*int*, *optional*) – Default gripping speed. Defaults to 100.
- **initialize** (*bool*, *optional*) – Register ROS publisher and subscriber on object instantiation. Defaults to False.
- **startup\_reset** (*bool*, *optional*) – Invoke internal reset on instantiation. Defaults to False.
- **calibrate** (*bool*, *optional*) – Adjust binary limits of gripper. Defaults to False.
- **bypass\_power** (*bool*, *optional*) – Ignoring power state monitor. Useful when gripper not attached to UR tool port. Defaults to False.

**Raises ValueError** – Invalid stroke width, must be 85mm or 140mm

**activate()** → None  
[summary]

**auto\_close**(*alt\_speed: Optional[int] = None, alt\_force: Optional[int] = None, blocking: bool = True*) → None  
Fully close the gripper or until obstructed.

#### Parameters

- **alt\_speed** (*int, optional*) – Override internal speed settings. Defaults to None.
- **alt\_force** (*int, optional*) – Override internal force settings. Defaults to None.
- **blocking** (*bool, optional*) – Wait until gripper motion is completed. Defaults to True.

**auto\_open**(*alt\_speed: Optional[int] = None, alt\_force: Optional[int] = None, blocking: bool = True*) → None  
Fully open the gripper or until obstructed.

#### Parameters

- **alt\_speed** (*int, optional*) – Override internal speed settings. Defaults to None.
- **alt\_force** (*int, optional*) – Override internal force settings. Defaults to None.
- **blocking** (*bool, optional*) – Wait until gripper motion is completed. Defaults to True.

**block()** → None  
Convenient snippet for idle looping until gripper finishes motion.

**calibrate()** → Tuple[int, int]  
Fully open and closes the gripper to record internal binary. Must be executed without any obstructions as this can dramatically influence gripper operations!

**Returns** lower and upper binary limit (default 0x00 to 0xFF or 0 to 255)

**Return type** (int, int)

**compensated\_publish**(*command: rvl\_robotiq\_controller.msg.\_Robotiq2FCommand.Robotiq2FCommand, lag: float = 0.1*)

Publish with a small wait between message for ROS topics to cope with the refresh rate of the gripper.

**deactivate()** → None  
Deactivate the gripper. Can also be used to clear the reset bit.

**grasp\_hard**(*opening: bool = False, alt\_speed: Optional[int] = None, blocking: bool = True*) → None  
Hard grasp preset, grasping with force set to maximum or 255 (approximately 235 N).

#### Parameters

- **opening** (*bool, optional*) – Grasp in the opening direction i.e. internal grasp. Defaults to False.
- **alt\_speed** (*int, optional*) – Override internal speed settings. Defaults to None.
- **blocking** (*bool, optional*) – Wait until gripper motion is completed. Defaults to True.

**grasp\_medium**(*opening: bool = False, alt\_speed: Optional[int] = None, blocking: bool = True*) → None  
Medium grasp preset, grasping with force set to 128 (approximately 128 N).

#### Parameters

- **opening** (*bool, optional*) – Grasp in the opening direction i.e. internal grasp. Defaults to False.
- **alt\_speed** (*int, optional*) – Override internal speed settings. Defaults to None.

- **blocking** (*bool*, *optional*) – Wait until gripper motion is completed. Defaults to True.

**grasp\_soft**(*opening: bool = False, alt\_speed: Optional[int] = None, blocking: bool = True*) → None  
Soft grasp preset, grasping with force set to 1 (approximately 20 N).

#### Parameters

- **opening** (*bool*, *optional*) – Grasp in the opening direction i.e. internal grasp. Defaults to False.
- **alt\_speed** (*int*, *optional*) – Override internal speed settings. Defaults to None.
- **blocking** (*bool*, *optional*) – Wait until gripper motion is completed. Defaults to True.

**grasp\_soft\_regrasp**(*opening: bool = False, alt\_speed: Optional[int] = None, blocking: bool = True*) → None

Soft grasp preset, grasping with force set to 1 (approximately 20 N) with Re-Grasp enabled.

#### Parameters

- **opening** (*bool*, *optional*) – Grasp in the opening direction i.e. internal grasp. Defaults to False.
- **alt\_speed** (*int*, *optional*) – Override internal speed settings. Defaults to None.
- **blocking** (*bool*, *optional*) – Wait until gripper motion is completed. Defaults to True.

**inps\_to\_raw\_speed**(*inps: Union[int, float]*) → int  
Convert inches/s to raw binary value [0-255]

**is\_holding**() → bool  
Returns true when the gripper is holding an object

**is\_moving**() → bool  
Returns true when the gripper is in motion

**lbf\_to\_raw\_force**(*lbf: Union[int, float]*) → int  
Convert lbf to raw binary value [0-255]

**mmps\_to\_raw\_speed**(*mmps: Union[int, float]*) → int  
Convert mm/s to raw binary value [0-255]

**newton\_to\_raw\_force**(*newton: Union[int, float]*) → int  
Convert N to raw binary value [0-255]

**open\_gripper**(*value: Union[int, float], alt\_speed: Optional[int] = None, alt\_force: Optional[int] = None, unit: str = 'mm', blocking: bool = True*) → None  
Open/Close the gripper to specified gap between the gripper pads.

#### Parameters

- **value** (*Union[int, float]*) – Width of the jaw opening.
- **alt\_speed** (*int*, *optional*) – Override internal speed settings. Defaults to None.
- **alt\_force** (*int*, *optional*) – Override internal force settings. Defaults to None.
- **unit** (*str*, *optional*) – Unit of measurement. Defaults to 'mm'.
- **blocking** (*bool*, *optional*) – Wait until gripper motion is completed. Defaults to True.

**open\_in\_to\_raw**(*inches: Union[int, float]*) → int  
Convert opening in inches to raw binary value [0-255]

**open\_mm\_to\_raw**(*mm: Union[int, float]*) → int  
Convert opening in mm to raw binary value [0-255]

**power\_monitor\_callback**(*msg*)

Callback for power subscriber

**raw\_force\_to\_lbf**(*raw: int*) → float

Convert raw value [0-255] to lbf

**raw\_force\_to\_newton**(*raw: int*) → float

Convert raw value [0-255] to N

**raw\_speed\_to\_inps**(*raw: int*) → float

Convert raw value [0-255] to in/s

**raw\_speed\_to\_mmpps**(*raw: int*) → float

Convert raw value [0-255] to mm/s

**raw\_to\_open\_in**(*raw: int*) → float

Convert raw value [0-255] to in of opening

**raw\_to\_open\_mm**(*raw: int*) → float

Convert raw value [0-255] to mm of opening

**register**(*timeout: int = 10*) → None

Register necessary ROS publishers and subscribers.

**Parameters** **timeout** (*int*, *optional*) – Wait time for topics to start publishing. Defaults to 10.

**report\_status**(*verbose: bool = False*) → None

Output the current state of the gripper.

**Parameters** **verbose** (*bool*, *optional*) – Display additional raw status message. Defaults to False.

**reset**() → None

Reset the gripper to default state (may or may not be obstructed).

**send\_raw\_position\_command**(*position: int, speed: int, force: int, blocking: bool = True*) → None

Send a position request command to the gripper ignoring internal settings.

**Parameters**

- **position** (*int*) – Raw position value [0-255].
- **speed** (*int*) – Raw speed value [0-255].
- **force** (*int*) – Raw force value [0-255].
- **blocking** (*bool*, *optional*) – Wait until gripper motion is completed. Defaults to True.

**set\_gripper\_force**(*value: Union[int, float], unit: str = 'N'*) → None

Set the internal (default) force setting of the gripper.

**Parameters**

- **value** (*Union[int, float]*) – New force value.
- **unit** (*str*, *optional*) – Unit of measurement. Defaults to 'N'.

**set\_gripper\_speed**(*value: Union[int, float], unit: str = 'mm/s'*) → None

Set the internal (default) speed setting of the gripper.

**Parameters**

- **value** (*Union[int, float]*) – New speed value.
- **unit** (*str*, *optional*) – Unit of measurement. Defaults to 'mm/s'.

**status\_monitor\_callback**(*msg*)

Callback for status subscriber

**class** rvl\_robotiq\_controller.RobotiqController.Robotiq3FController

Bases: object

**\_\_init\_\_**()

## rvl\_robotiq\_modbus\_server package

### Submodules

#### rvl\_robotiq\_modbus\_server.RobotiqModbusServer module

**class** rvl\_robotiq\_modbus\_server.RobotiqModbusServer.RobotiqRTUClient(*unit\_id=9*,  
*input\_addr=1000*,  
*output\_addr=2000*)

Bases: object

**\_\_init\_\_**(*unit\_id=9*, *input\_addr=1000*, *output\_addr=2000*)

**connect**(*device\_addr*, *delay=1*)

**disconnect**()

**parse\_registers**(*recv\_regs*, *nregs*)

**request\_status**(*nbytes=6*)

**send\_command**(*command*)

**class** rvl\_robotiq\_modbus\_server.RobotiqModbusServer.RobotiqTCPClient

Bases: object

**\_\_init\_\_**()

## 2.3.2 UR Dashboard Control

### rvl\_ur\_remote\_dashboard ROS Package

#### rvl\_ur\_motion\_planner package

### Submodules

#### rvl\_ur\_motion\_planner.URMoveitCommander module

**class** rvl\_ur\_motion\_planner.URMoveitCommander.URCommander(*group\_name='arm'*, *speed=0.1*,  
*accel=0.1*)

Bases: object

**\_\_init\_\_**(*group\_name='arm'*, *speed=0.1*, *accel=0.1*)

**all\_close**(*goal*, *actual*, *tolerance*)

Convenience method for testing if the values in two lists are within a tolerance of each other. For Pose and PoseStamped inputs, the angle between the two quaternions is compared (the angle between the identical



orientations  $q$  and  $-q$  is calculated correctly). @param: goal A list of floats, a Pose or a PoseStamped  
@param: actual A list of floats, a Pose or a PoseStamped @param: tolerance A float @returns: bool

```
define_preset_locations()
go_to_preset_location(name)
home()
report()
```

## rvl\_ur\_remote\_dashboard package

### Submodules

#### rvl\_ur\_remote\_dashboard.URInterfaceMapping module

```
class rvl_ur_remote_dashboard.URInterfaceMapping.RobotModeMapping(value)
```

Bases: enum.Enum

An enumeration.

```
BACKDRIVE = 6
BOOTING = 2
CONFIRM_SAFETY = 1
DISCONNECTED = 0
IDLE = 5
NO_CONTROLLER = -1
POWER_OFF = 3
POWER_ON = 4
RUNNING = 7
UPDATING_FIRMWARE = 8
```

```
class rvl_ur_remote_dashboard.URInterfaceMapping.SafetyModeMapping(value)
```

Bases: enum.Enum

An enumeration.

```
AUTOMATIC_MODE_SAFEGUARD_STOP = 12
FAULT = 9
NORMAL = 1
PROTECTIVE_STOP = 3
RECOVERY = 4
REDUCED = 2
ROBOT_EMERGENCY_STOP = 7
SAFEGUARD_STOP = 5
SYSTEM_EMERGENCY_STOP = 6
SYSTEM_THREE_POSITION_ENABLING_STOP = 13
```

**UNDEFINED\_SAFETY\_MODE = 11**

**VALIDATE\_JOINT\_ID = 10**

**VIOLATION = 8**

**class** rvl\_ur\_remote\_dashboard.URInterfaceMapping.**SetIOFunctionMapping**(*value*)

Bases: enum.Enum

An enumeration.

**SET\_ANALOG\_OUT = 3**

**SET\_DIGITAL\_OUT = 1**

**SET\_FLAG = 2**

**SET\_TOOL\_VOLTAGE = 4**

**class** rvl\_ur\_remote\_dashboard.URInterfaceMapping.**SetIOPinMapping**(*value*)

Bases: enum.Enum

An enumeration.

**class** rvl\_ur\_remote\_dashboard.URInterfaceMapping.**SetIOPinState**(*value*)

Bases: enum.Enum

An enumeration.

**OFF = 0**

**ON = 1**

**class** rvl\_ur\_remote\_dashboard.URInterfaceMapping.**SetIOToolState**(*value*)

Bases: enum.Enum

An enumeration.

**TOOL\_VOLTAGE\_0V = 0**

**TOOL\_VOLTAGE\_12V = 12**

**TOOL\_VOLTAGE\_24V = 24**

## rvl\_ur\_remote\_dashboard.URRemoteDashboard module

**class** rvl\_ur\_remote\_dashboard.URRemoteDashboard.**URRemoteDashboard**(*name: str = 'UR5e',*  
*using\_gripper: bool = False,*  
*using\_urscript: bool = False,*  
*service\_timeout: int = 5)*

Bases: object

**\_\_init\_\_**(*name: str = 'UR5e', using\_gripper: bool = False, using\_urscript: bool = False, service\_timeout: int = 5*) → None

The UR Remote Dashboard class. This is the primary extension overlaying the existing Universal Robot Driver code base to access mapped services.

### Parameters

- **name** (*str, optional*) – Readable name to identify controller. Defaults to ‘UR5e’.
- **using\_gripper** (*bool, optional*) – Initialized the attached Robotiq gripper. Defaults to False.

- **using\_urscript** (*bool*, *optional*) – Register appropriate publisher to send UR Script. Defaults to False.
- **service\_timeout** (*int*, *optional*) – Wait time for services to come on. Defaults to 5.

**clear\_operational\_mode**() → bool

Allow PolyScope to change operational mode. User password will be enabled.

**clear\_protective\_stop**(*timeout: int = 30*) → bool

Clear a protective stop.

**close\_popup**(*safety: bool = False*) → bool

Close a popup on the Teach Pendant or PolyScope.

**Parameters** **safety** (*bool*, *optional*) – Set to True if popup is a safety popup. Defaults to False.

**Returns** True if the targeted popup is closed.

**Return type** bool

**cold\_boot**() → bool

Go directly to operational state (power on, brakes released). See `release_brakes()`.

**connect\_dashboard**(*quiet: bool = False*) → bool

Connect to the dashboard server. Need to be done before calling other services.

**define\_services**()

**disconnect\_dashboard**() → bool

Disconnect from the dashboard server.

**get\_loaded\_program**() → Optional[str]

Returns the name of the loaded program.

**get\_robot\_mode**() → Optional[int]

Returns the current robot mode.

**get\_safety\_mode**() → Optional[int]

Returns the current safety mode.

**is\_program\_running**() → bool

Returns true if the default or loaded program is running.

**is\_program\_saved**() → bool

Returns true if the default or loaded program is saved.

**load\_program**(*filename: str, ptype: str, wait: int = 10, attempts: int = 10*) → None

Load a program or installation file.

**Parameters**

- **filename** (*str*) – Name of file with extension e.g., program.urp
- **ptype** (*str*) – Type of program. Accepting ['prog', 'p', 'program', 'urp'] or ['inst', 'i', 'installation'].
- **wait** (*int*, *optional*) – Wait time to handle known disconnection issue. Defaults to 10.
- **attempts** (*int*, *optional*) – Number of reconnection attempts. Defaults to 10.

**log\_to\_pendant**(*message: str*) → None

Log a message to PolyScope logs.

**pause\_loaded\_program**() → bool

Pause PolyScope program execution.

**power\_off\_arm**(*timeout: int = 30*) → bool

Power off the arm.

**power\_on\_arm**(*timeout: int = 30*) → bool

Power on the arm to idle state (brakes engaged).

**query\_program\_state**() → None

Display the name and execution state of the current PolyScope program.

**raw\_request**(*query*)

Send any arbitrary message or request to the dashboard server.

**register\_robot\_status**() → None

Register necessary subscribers and callbacks to monitor robot operational status.

**release\_brakes**(*timeout: int = 30*) → bool

Fully power on the robot with brakes released.

**restart\_safety**() → bool

Clear a safety fault or violation. Arm will be powered off.

**robot\_iostate\_callback**(*msg*)

**robot\_safety\_callback**(*msg*)

**robot\_status\_callback**(*msg*)

**send\_popup**(*message: str*) → bool

Send a message as a popup to Teach Pendant or PolyScope.

**set\_io**(*function: int, pin: int, state: float*) → None

Set specific IO port on the robot. Currently not supporting specific domains (current/voltage).

#### Parameters

- **function** (*int*) – See SetIOFunctionMapping.
- **pin** (*int*) – Which pin to execute the function on.
- **state** (*float*) – 0/1 for digital IOs and value for analog IO.

**set\_payload**(*mass: float, cx: float, cy: float, cz: float*) → None

Set the payload mass and center of gravity.

#### Parameters

- **mass** (*float*) – Mass of the payload in kg.
- **cx** (*float*) – Center of gravity of the payload.
- **cy** (*float*) – Center of gravity of the payload.
- **cz** (*float*) – Center of gravity of the payload.

**set\_speed\_slider**(*fraction: float*) → None

Set robot execution speed as a fraction. Only set less than 1 on scaled controllers.

**Parameters** **fraction** (*float*) – 0 to 1 if using scaled (default) controllers.

**spam\_connect**(*attempts: int = 10*) → bool

Repeatedly calling connect() due to error prone and asynchronous status of the server.

**Parameters** **attempts** (*int, optional*) – Number of times connect() is called internally. Defaults to 10.

**start\_loaded\_program**() → bool

Start execution of default or loaded program.

**stop\_loaded\_program()** → bool  
Stop PolyScope program execution.

**system\_shutdown()** → None  
Fully power down the robot (including control box).

**terminate\_external\_control()** → bool  
Make the external\_control node on PolyScope returns.

**trigger\_service(serv\_alias)**  
Internal trigger service handling with exceptions

**verify\_services()**

**zero\_force\_torque\_sensor()** → bool  
Zero the ft-sensor. Only work on e-Series in remote-control mode.

### 2.3.3 Utilities

#### rvl\_utilities ROS Package

#### rvl\_utilities package

#### Submodules

#### rvl\_utilities.CustomLogger module

```
class rvl_utilities.CustomLogger.ColorLogger(label=None)
    Bases: object
    __init__(label=None)
    define_sequences()
    gen_output_str(msg, esc, indent=0)
    log_error(msg, indent=0)
    log_info(msg, indent=0)
    log_success(msg, indent=0)
    log_warn(msg, indent=0)
rvl_utilities.CustomLogger.gen_ansi_rgb_esc(code)
rvl_utilities.CustomLogger.gen_esc(code)
rvl_utilities.CustomLogger.hex_to_rgb(hex, ansi=True)
rvl_utilities.CustomLogger.rgb_to_hex(rgb)
```



## REFERENCES

The bulk of the driver is written based on old or current work, with some additional tweaks and tricks collected from browsing Universal Robot and Robotiq. Since it is quite haphazard, this is a tentative list of references and will be growing as I can recollect more of where they came from.

- [UniversalRobots/Universal\\_Robots\\_ROS\\_Driver](#)
- [ros-industrial/robotiq](#)
- [IntelRealSense/realsense-ros](#)
- [MoveIt! Motion Planning Framework](#)
- [Blog post by jproberge](#), last maintainer of ROS Industrial Robotiq repository.
- [Numerous ROS tutorials](#)





## **LICENSE**

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A nice tl;dr is provided [here](#).

**Warning:** As always when working with any robot, safety is only as safe as the human can make it. So please, **proceed with caution**.

### **4.1 Apache 2.0 Boilerplate**

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## CHANGELOG

### 5.1 Releases

#### 5.1.1 0.0.1-alpha - 2022/FEB/01

- Initial release of driver components: UR Remote Dashboard and Robotiq Controller
- Support for rudimentary forward and inverse kinematics
- Added pre-built Docker Image

### 5.2 Tasks

Don't worry if there's nothing here. I'm sure there's more...



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