RUNNING OUR SYSTEM

simulation:
```
$ roslaunch sr_hand
gazebo_arm_and_hand.launch
```

gui:
```
$ rosrun rqt_gui rqt_gui
```

examples:
```
$ rosrun sr_example
shadowhand_publisher.py
```

SENDING DATA

Moving ffj3:
```
$ rostopic pub
/sh_ffj3_position_controller/command
std_msgs/Float64 1.5
```

READING DATA

reading current joints states:
```
$ rostopic echo /joint_states
```
reading tactile data:
```
$ rostopic echo /contacts/ff/distal
```

ADDITIONAL TOOLS

Go to the examples directory:
```
$ roscd sr_example
```
List all topics:
```
$ rostopic list
```

Get more information on a topic:
```
$ rostopic info /topic_name
```

Plot ffj3 position
```
$ rqt_plot
/sh_ffj3_position_controller/state/proc
ess_value
```