

Starting up Baxter: (from the cwru_baxter "README")
November, 2015

- 1) Make sure that Baxter's power, e-stop, and network cable are all plugged in and ready to go.
- 2) Turn Baxter on by pressing the power button on the side.
- 3) Wait for a while until the LED halo around Baxter's head is GREEN.

4) from the development workstation, open a terminal and run:
 `export ROS_MASTER_URI="http://011503P0031:11311"`

OR `export ROS_MASTER_URI = "http://baxter01:11311"`

OR, on our machines, there is an alias you can run:

`baxter_master`

This must be done in *every* terminal from which you run ROS code.

This will set up Baxter as the ROS "master", and your workstation will use the roscore that is running on Baxter.

- 5) enable the robot to respond to motion commands with:
 `roslaunch baxter_tools enable_robot.py -e`

- 6) Start the CWRU joint-interpolation action server:
 `roslaunch baxter_traj_streamer traj_interpolator_as`

Baxter is now ready to receive goal requests from a client (see, e.g.
`baxter_traj_streamer/traj_action_client_pre_pose`)