

## BAXTER BRIEF SUMMARY HW & SW 3\_2\_3

1. This page serves as a lookup reference for all the hardware and functionality on the Baxter Research SDK robot. The main interface of the Baxter RSDK is via ROS Topics and Services, which you will find listed and described below along with other core information needed to interface with Baxter. (Note the Robot and Simulator Tabs!)

[http://sdk.rethinkrobotics.com/wiki/API\\_Reference](http://sdk.rethinkrobotics.com/wiki/API_Reference)

2. The baxter\_interface repository holds our python API for interacting with the Baxter Research Robot. This comprises of a set of classes that provide wrappers around the ROS communications from Baxter, allowing for direct python control of the different interfaces of the robot.

[http://sdk.rethinkrobotics.com/wiki/Baxter\\_Interface](http://sdk.rethinkrobotics.com/wiki/Baxter_Interface)

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