

ARM CONTROL MODES: BAXTER, SAWYER

BAXTER:

http://sdk.rethinkrobotics.com/wiki/Arm_Control_Modes

Fundamental to the operation of Baxter via the SDK is a familiarity with the available joint control modes. The joint control modes define the 'modes' in which we can control Baxter's limbs in joint space. These are provided via a ROS message API: ([baxter_core_msgs/JointCommand.msg](#))

SAWYER:

http://sdk.rethinkrobotics.com/intera/Arm_Control_Systems

Contents

1 Control Overview

- [1.1 Joint Command Overview](#)
 - [1.2 Motion Controller Interface Overview](#)
 - [1.3 RealTime Motor Controller](#)
- [2 Joint Control Modes](#)
 - [2.1 Message Definition](#)
 - [2.2 Joint Control Fundamentals](#)
 - [2.3 Joint Position Control](#)
 - [2.4 Joint Trajectory-Position Control](#)
 - [2.5 Joint Velocity Control](#)
 - [2.6 Joint Torque Control](#)
 - [2.7 Joint Command Timing](#)
- [3 Motion Controller Interface](#)
 - [3.1 ROS Action Server](#)
 - [3.2 Trajectory Interpolation: Joint vs. Cartesian](#)
 - [3.3 Possible Errors](#)
 - [3.4 Trajectory Message](#)
 - [3.5 Motion Trajectory](#)
 - [3.6 Motion Waypoint](#)
 - [3.7 Motion Waypoint Options](#)
 - [3.8 Interaction Options](#)
- [4 Interaction Control Mode](#)
 - [4.1 Impedance Control Concept](#)
 - [4.2 Force Control Concept](#)
 - [4.3 Interaction Control Overview](#)
 - [4.4 Interaction Control Command](#)
 - [4.4.1 Message Definition](#)
- [5 Joint Trajectory Action Server](#)
 - [5.1 JTAS Modes](#)

- [5.1.1 Velocity Mode](#)
- [5.1.2 Position Mode](#)
- [5.1.3 Inverse Dynamics Feed Forward Position Mode \(using Joint Trajectory Position Mode\)](#)
- [6 Collision Avoidance](#)
- [7 Collision Detection](#)
- [8 Gravity Compensation Torques](#)
- [9 Zero-G mode](#)