

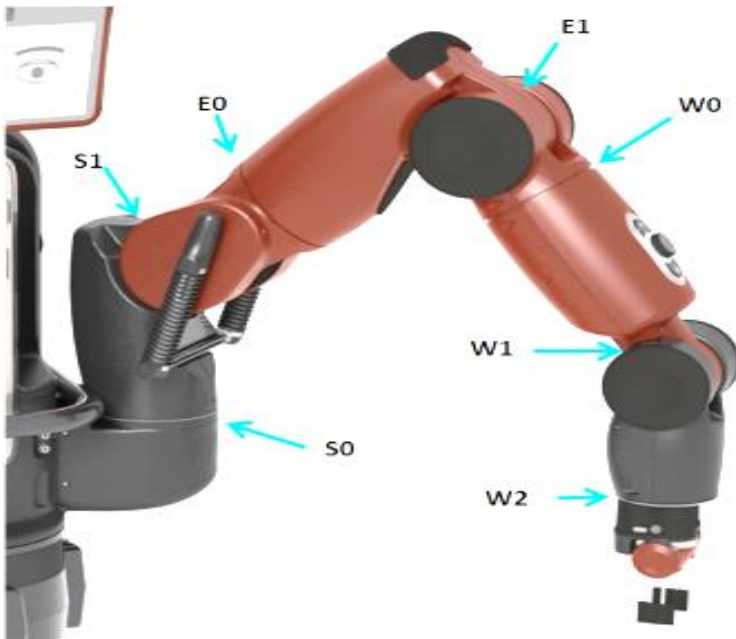
01/23/15 Joint Position Keyboard Example - This example demonstrates numerous joint position control.

View Video

Baxter Research Robot Examples: Joint Position Using Keyboard

1. Power on Baxter - white button on rear
2. LOG ON Workstation
3. Go to `~/ros_ws` (ROS workspace)
4. `./baxter.sh`
5. `roslaunch baxter_tools enable_robot.py -e`
6. `roslaunch baxter_examples joint_position_keyboard.py`

TYPE ? FOR LIST OF COMMAND KEYS TO MOVE JOINTS WITH NAMES SHOWN IN FIGURE:



EXAMPLE AT TERMINAL WINDOW

```
tlharmanphd@D125-43873:~$ cd ~/ros_ws
```

```
tlharmanphd@D125-43873:~/ros_ws$ ./baxter.sh
```

```
[baxter - http://172.29.64.200:11311] tlharmanphd@D125-43873:~/ros_ws$ roslaunch baxter_tools enable_robot.py -e
```

```
[INFO] [WallTime: 1422042340.373074] Robot Enabled
```

```
[baxter - http://172.29.64.200:113
```

```
1] tlharmanphd@D125-43873:~/ros_ws$ roslaunch baxter_examples joint_position_keyboard.py
```

```
Initializing node...
```

```
Getting robot state...
```

```
Enabling robot...
```

```
[INFO] [WallTime: 1422042352.890294] Robot Enabled
```

```
[WARN] [WallTime: 1422042353.064890] left_gripper electric: Gripper Firmware version (3.0.0 5.5)
```

does not match SDK Version (1.0.0). Use the Robot's Field-Service-Menu to Upgrade your Gripper Firmware.

Controlling joints. Press ? for help, Esc to quit.

key bindings:

Esc: Quit

?: Help

/: left: gripper calibrate

,: left: gripper close

m: left: gripper open

y: left_e0 decrease

o: left_e0 increase

u: left_e1 decrease

i: left_e1 increase

6: left_s0 decrease

9: left_s0 increase

7: left_s1 decrease

8: left_s1 increase

h: left_w0 decrease

l: left_w0 increase

j: left_w1 decrease

k: left_w1 increase

n: left_w2 decrease

:: left_w2 increase

RIGHT

b: right: gripper calibrate

c: right: gripper close

x: right: gripper open

q: right_e0 decrease

r: right_e0 increase

w: right_e1 decrease

e: right_e1 increase

1: right_s0 decrease

4: right_s0 increase

2: right_s1 decrease

3: right_s1 increase

a: right_w0 decrease

f: right_w0 increase

s: right_w1 decrease

d: right_w1 increase

z: right_w2 decrease

v: right_w2 increase