

gripper_control.cpp

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This example demonstrates how to control the gripper (end-effector) position. The gripper is controlled by specifying its open/close position in meters. A higher value means a more open gripper, while a lower value closes it.

Recommended value range: (fully closed) to (fully open). Values outside this range may lead to unexpected behavior.

Example usage:

```
#include "airbot_sdk.hpp"
using namespace airbot;

int main() {
    auto sdk = std::make_shared<AirbotSdk>("192.168.0.xxx", 50051);

    // Control gripper position in meters (recommended range: 0.0 ~ 0.07)
    sdk->MoveEefPos(0.07); // Fully open the gripper

    return 0;
}
```