

robot_mode.hpp File Reference

Defines control modes for robot arm operations. [More...](#)

```
#include <cstdint>
```

Include dependency graph for robot_mode.hpp:

This graph shows which files directly or indirectly include this file:

[Go to the source code of this file.](#)

Namespaces

namespace `airbot`

Namespace containing all Airbot SDK related definitions.

Enumerations

```
enum class airbot::RobotMode : int {  
    airbot::PLANNING_POS = 10 , airbot::PLANNING_WAYPOINTS_PATH =  
    11 , airbot::PLANNING_WAYPOINTS = 12 , airbot::SERVO_JOINT_POS  
    = 20 ,  
    airbot::SERVO_CART_POSE = 21 , airbot::SERVO_JOINT_VEL = 24 ,  
    airbot::SERVO_CART_TWIST = 25 , airbot::MIT_INTEGRATED = 80 ,  
    airbot::GRAVITY_COMP = 90 , airbot::INACTIVE = 98 ,  
    airbot::UNDEFINED = 99  
}
```

Enum class representing the control modes of the robot arm. [More...](#)

Detailed Description

Defines control modes for robot arm operations.

This file defines various control modes used by the robot arm. Each mode represents a distinct behavior or command interface for controlling the robot.

Modes are grouped into:

- Planning modes
- Servo control modes (in joint/cartesian space)
- Special modes like gravity compensation or inactive state