.bashrc files

.bashrc for Jetson

```
# CUSTOM OPENCV
export LD_LIBRARY_PATH=/usr/local/opencv_v4.5.5/lib:$LD_LIBRARY_PATH

# ROS
export ROS_HOME=/home/slamr01/workspace/ros_home
# for running independently:
#export ROS_MASTER_URI=http://localhost:11311
#export ROS_IP=127.0.0.1
# for running with remote PC:
export ROS_MASTER_URI=http://192.168.3.2:11311
export ROS_IP=192.168.3.2
source /opt/ros/noetic/setup.bash
source ${HOME}/workspace/catkin_ws/devel/setup.bash

# fix for forcing audio through Jetson when connecting to Jetson by remote ssh
alias force_audio='xprop -root -f PULSE_SERVER 8s -set PULSE_SERVER {dbfef1aa0b064bcf9d30ec3ad0886edb}unix:/run
/user/1000/pulse/native'
force_audio

# rosbag recording for human subjects
export OBSTACLE_TOPICS="/tf /tf_static /rtabmap/localization_pose /republish/0_rrt_pre_smooth /device_base/goal
/core/nav_traversed_path /core/nav_starts /core/nav_stops /core/nav_stats"

# set output resolution to 720x480 for interfacing with Argus
alias set_argus_resolution='xrandr --auto --output DP-1 --mode 720x480'

# Argus Video Interface
# uncomment the line below when launching application remotely over ssh in order to make the OpenCV window open
on the Argus
# display rather than on the remote display
# this also provides the benefit of opening the xterm windows on the Jetson desktop, which prevents these
popups from stealing
# keyboard focus from the remote terminal used to start the application (with the drawback that you can't see
the outputs to the
# xterm windows from the remote system in case of an error condition)
export DISPLAY=:1
```

.bashrc for remote laptop

```
# CUDA
export PATH=/usr/local/cuda-12.2/bin${PATH:+:${PATH}}
export LD_LIBRARY_PATH=/usr/local/cuda-12.2/lib64${LD_LIBRARY_PATH:+:${LD_LIBRARY_PATH}}

# ENET
alias enet_share='~/ENET_share.sh setup 192.168.3.0/24'
alias vpn='sudo openconnect gpvpn.jhuapl.edu --protocol=gp'

# OpenCV
export LD_LIBRARY_PATH=/usr/local/opencv_v4.5.5/lib:$LD_LIBRARY_PATH

# ROS
source /opt/ros/noetic/setup.bash
source /home/slamr01/workspace/catkin_ws/devel/setup.bash

# For running ROS Master remotely on jetson
#export ROS_MASTER_URI=http://localhost:11311
#export ROS_IP=127.0.0.1
export ROS_MASTER_URI=http://192.168.3.2:11311
export ROS_IP=192.168.3.101

# aliases for jetson
alias sshjetson="sshpass -pslamr01 ssh -X slamr01@192.168.3.2"
alias apl_ros='export ROS_MASTER_URI=http://192.168.3.2:11311 && export ROS_IP=10.132.193.166'
alias jetson_ros='export ROS_MASTER_URI=http://192.168.3.2:11311 && export ROS_IP=192.168.3.101'
```