

A2-W Simulation Record

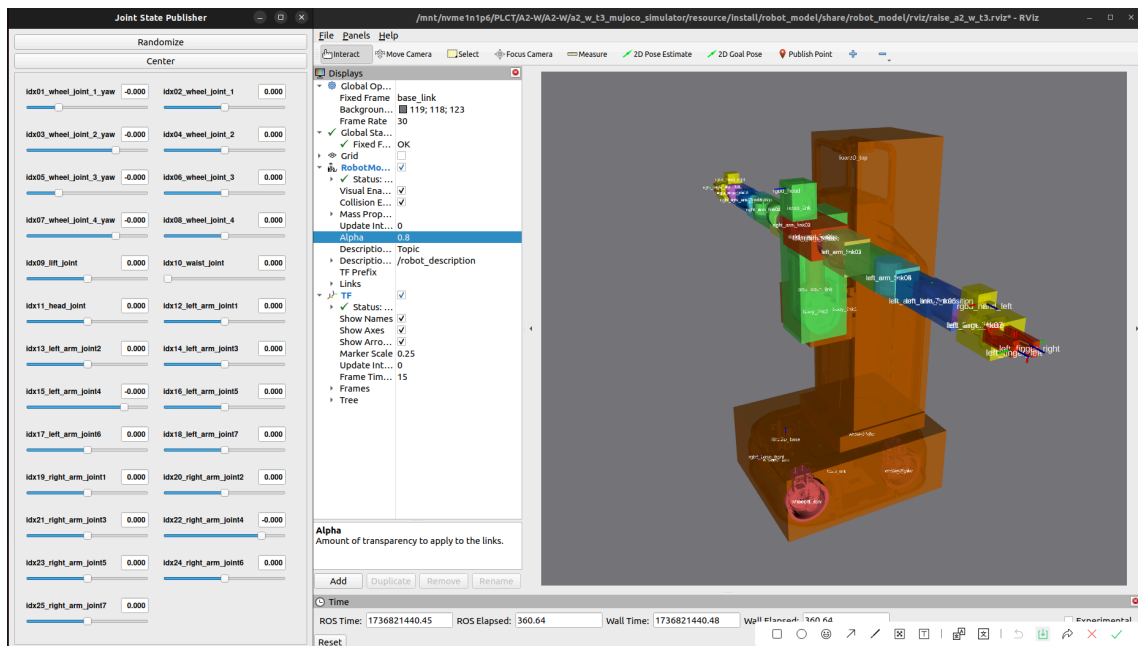
publish robot model to rviz

1. build the package with colcon in folder `resource` :

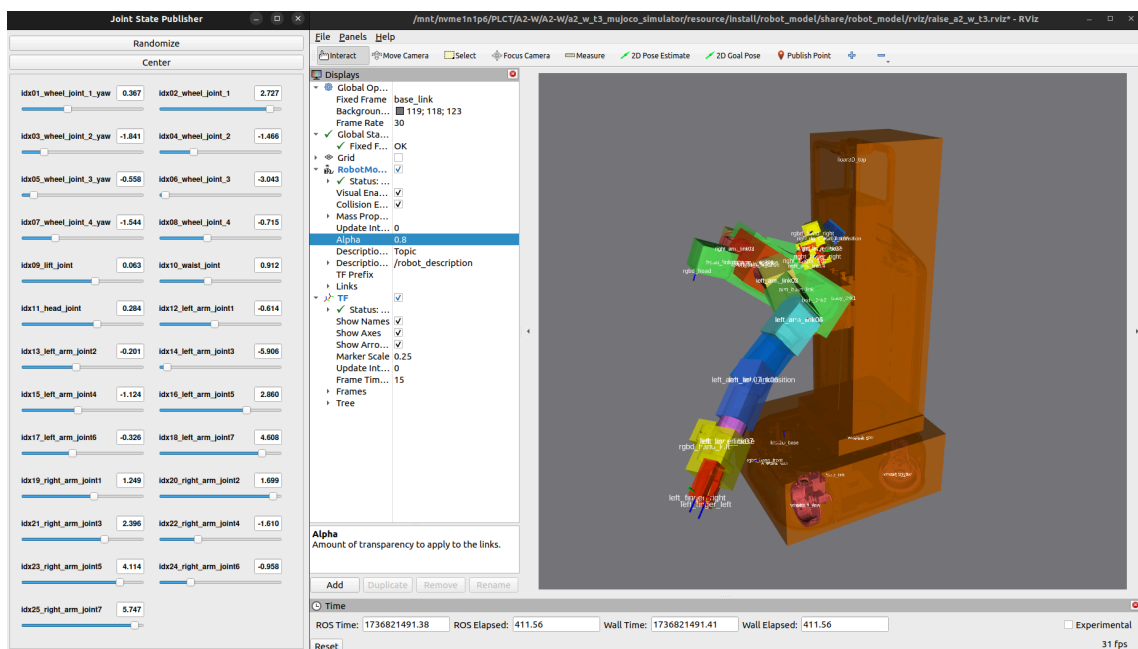
```
cd <path to a2_w_t3_mujoco_simulator/resource>
colcon build --symlink-install
```

2. launch ros2 package `robot_model` to publish robot model

```
ros2 launch robot_model raise_a2_w_t3.launch.py debug_urdf:=true
```



3. able to modify robot state with Joint State publisher gui



publish robot model to mujoco

1. install gcc-12 and g++-13

```
sudo apt-get update
sudo apt-get install gcc-13 g++-13
```

2. launch bash script under folder `bin`

```
cd <path to a2_w_t3_mujoco_simulator/bin>
./start_sim.sh -s
```

```
kunama@kunama-Lenovo-Legion-R7000-2020:bin$ ./start_sim.sh -s
Selected configuration directory:
No configuration directory specified. Using default: /mnt/nvme1n1p6/PLCT/A2-W/A2-W/a2_w_t3_mujoco_simulator/bin/./configuration
Please select a robot:
0: raise_a2_w_t3
Please enter your choice: 
```

choose `raise_a2_w_t3`

