

تنشيط وتشغيل باكج الذراع على نظام ROS

١- تنشيط نظام ROS

٢- نروح لموجة الأوامر ونكتب :

```
3- rosdep update
4-
5- sudo apt-get install ros-noetic-catkin
6-
7- mkdir -p ~/catkin_ws/src
8-
9- cd ~/catkin_ws/
10-
11- catkin_make
12-
13- cd ~/catkin_ws/src
14-
15- git clone https://github.com/smart-
    methods/arduino_robot_arm.git
16-
17- cd ~/catkin_ws
18-
19- rosdep install --from-paths src --ignore-src -r -y
20-
21- sudo apt-get install ros-kinetic-moveit
22-
23- sudo apt-get install ros-kinetic-joint-state-publisher ros-
    kinetic-joint-state-publisher-gui
24-
25- sudo apt-get install ros-kinetic-gazebo-ros-control joint-
    state-publisher
26-
27- sudo apt-get install ros-kinetic-ros-controllers ros-kinetic-
    ros-control
28-
29- sudo nano ~/.bashrc
30-
31- at the end of the (bashrc) file add the follwing line
32- (source /home/الاسم النظام/catkin_ws/devel/setup.bash)
33- then
34- ctrl + o
35-
36- source ~/.bashrc
37-
38- roslaunch robot_arm_pkg check_motors.launch
```

