# README

## For Additional Project 1 and 2 below: projectPublisher & projectSubscriber
ROS Command - This code is meant to be implemented with the husky robot

1. To run the **projectPublisher**.py code with the husky robot on gazebo simulator, we can follow the following steps:
   a. Run roscore on a different terminal
   b. Run source ~/catkin_ws/devel/setup.bash (A good practice)
   c. On a different terminal, at the script level "roscd scripts" Run chmod +x *.py
   d. In cd catkin_ws, we will source the devel setup.bash file with the code - source/devel/setup.bash
   e. The projectPublisher.py can be run using the code - rosrun my_robot_tuturial projectPublisher.py
   f. Then launch the husky robot with gazebo using the code - roslaunch husky_gazebo husky_playpen.launch

All things being equal the robot will be moving with the code on the gazebo simulator.

2. To run the **projectPublisher**.py and **projectSubscriber**.py, with the following steps:
   a. Run roscore on a different terminal
   b. Run source ~/catkin_ws/devel/setup.bash (A good practice)
   c. On a different terminal, at the script level "roscd scripts" Run chmod +x *.py
   d. At the scripts level, run "rosrun my_robot_tutorial projectSubscriber.py"
   e. On another terminal, at the scripts level, run - rostopic pub -r 10 /topic_1 std_msgs/Float32 "data:1.0"
   f. On a different terminal, at the scripts level, run - rostopic pub -r 10 /topic_2 std_msgs/Float32 "data:2.0"

# For Other Projects

## For Other Project done in the class:
If all things being equal the robot will be moving with the code on the gazebo simulator.

3. To run the **X_Publisher**.py and **X_Subscriber**.py, with the following steps:
   a. Run roscore on a different terminal
   b. Run source ~/catkin_ws/devel/setup.bash (A good practice)
   c. On a different terminal, at the script level "roscd scripts" Run chmod +x *.py
   d. At the scripts level, run "rosrun my_robot_tutorial X_Subscriber.py"
   e. On another terminal, at the scripts level, run "rosrun my_robot_tutorial X_Publisher.py"
   f. *Run any other special code as started in the class*

**X_Subscriber & X_Publisher are any of the pair below:**

- Follow similar step with the steps above and run action_client.py and action_server.py together
- Follow similar step with the steps above and run odd_even_server.py and odd_even_client.py
- Follow similar step with the steps above and run turn_camera_service.py and turn_camera_client.py
- Follow similar step with the steps above and run publisher.py and subscriber.py
- Follow similar step with the steps above and run turn_camera_service.py and turn_camera_client.py