### **World/Launch Documentation**

The project has a launch file required to run the project. Below is the launch file called p2.launch

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| --- |
| <**launch**>  <!-- PROJECT NODE -->  <**node** pkg="cs5023\_rip\_opportunity" type="cs5023\_rip\_opportunity.py" name="cs5023\_rip\_opportunity" output="screen"/> </**launch**> |

The file launches out python code

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| --- |
| <**node** pkg="cs5023\_rip\_opportunity" type="cs5023\_rip\_opportunity.py" name="cs5023\_rip\_opportunity" output="screen"/> |

The above code runs our python files and package so the turtlebot will run based on the conditions we programmed, according to the project 2 description.

### **Instructions on running project on a computer**

* Download and make sure you have all the files.
* SSH into the turtlebot computer; this should be common knowledge.
* Open up the terminal.
* Make a catkin folder with the following command: “*mkdir catkin\_ws”.*
* Make a directory called **src** in the **catkin\_ws** directory**.**
* Go back to the **catkin\_ws** directory and then type the following command: “*catkin\_make”.*
* Type the following command: “*source devel/setup.bash”*
* Go to the **src** directory.
* Move the **cs5023\_rip\_opportunity** directory into the **src** directory.
* Go back to the **catkin\_ws** directory.
* Now, you should be able to run the command “*roslaunch cs5023\_rip\_opportunity p2.launch”.* Then the robot should start moving in the real world.
* The robot should move according to the project 2 description.
* On the terminal you can observe the actions of the robot.
* From there, you can exit or move the turtlebot in the real world.