

Theory

- ## Exercise

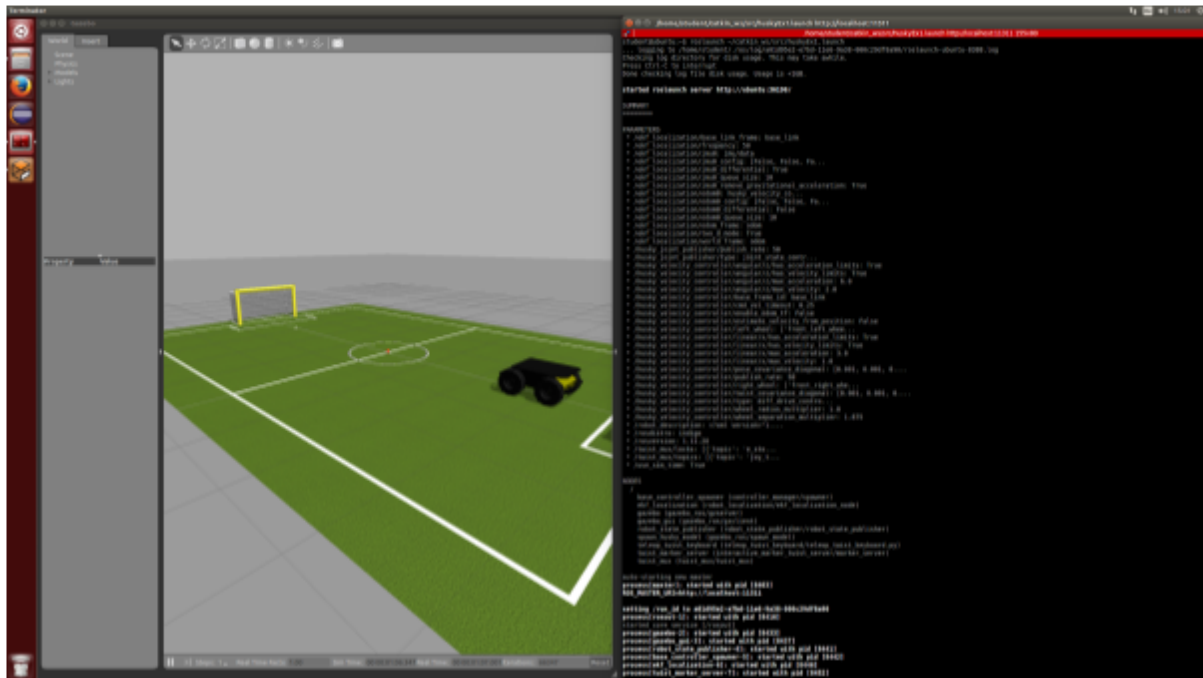
1. Setup the Husky simulation:
http://wiki.ros.org/husky_gazebo/Tutorials/Simulating%20Husky
2. Launch the simulation and inspect the created nodes and their topics using:

```
roscpp launch husky_gazebo  
rostopic list  
rostopic echo [TOPIC]  
rostopic hz [TOPIC]  
rqt graph
```

<http://wiki.ros.org/rostopic>
<http://wiki.ros.org/rosnode>

3. Command a desired velocity to the robot from the terminal (`rostopic pub [TOPIC]`)
4. Use **teleop_twist_keyboard** to control your robot using the keyboard. Find it online and compile it from source! Use `git clone`.
For a short git overview see:
http://rogerdudler.github.io/git-guide/files/git_cheat_sheet.pdf

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Left: Gazebo with Robocup14 World, Right: First lines of output when starting the launch file you have to set up

Evaluation

- ❑ Check if teleop_twist_keyboard is compiled from source (rosed teleop_twist_keyboard should show the git folder) [40%]
- ❑ Start the launch file. This should bring everything up that's needed to drive Husky with the keyboard as shown in the above image. [60%]