

1.Before using ROS, you need to ensure that you have installed the Rosmaster driver library, as described in Section 3 of the Python Basic Control Course

2.Create, initialize, and compile a ROS workspace (for example, Driver_ws)

terminal input

```
mkdir driver_ws
cd driver_ws
mkdir src
cd src
catkin_init_workspace
cd ..
catkin_make
```

3.Paste the contents of the SRC folder in the feature pack folder into the SRC folder in the ROS workspace

```
cd ~/driver_ws/src
```

4.Back to the workspace directory, the terminal type catkin_make to compile the workspace

```
cd ~/driver_ws
catkin_make
```

5.Complete the compilation with no errors

Note: if you have a pre-created workspace, just copy the SRC content to the workspace SRC file and compile it under the workspace directory catkin_make.