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

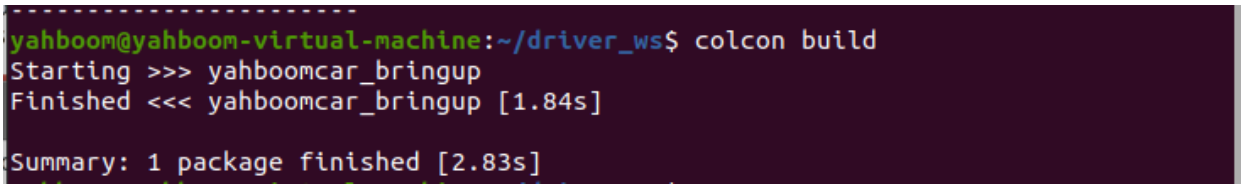
2、Create, initialize, and compile a ROS workspace (for example, driver_ws)

terminal input,

```
mkdir driver_ws
cd    driver_ws
mkdir src
cd src
```

3、Copy and paste all the feature pack folders under the folder into the src folder of the ROS workspace, and then return to the driver_ ws, enter the following command to compile,

```
colcon build
```



4、Add feature pack path to environment variable

terminal input,

```
sudo gedit ./.bashrc
```

Paste the content below to the end of the file,

```
source ~/driver_ws/install/setup.bash
```

5、Save and exit, enter the following command to refresh the environment variables

```
source ~/.bashrc
```

6、Compilation may require installation of dependencies

```
#Taking ros foxy as an example
sudo apt install ros-foxy-geographic-*
sudo apt install libgeograph*
```