准备工作：

ubuntu 20.04 + ROS2 - foxy - desktop

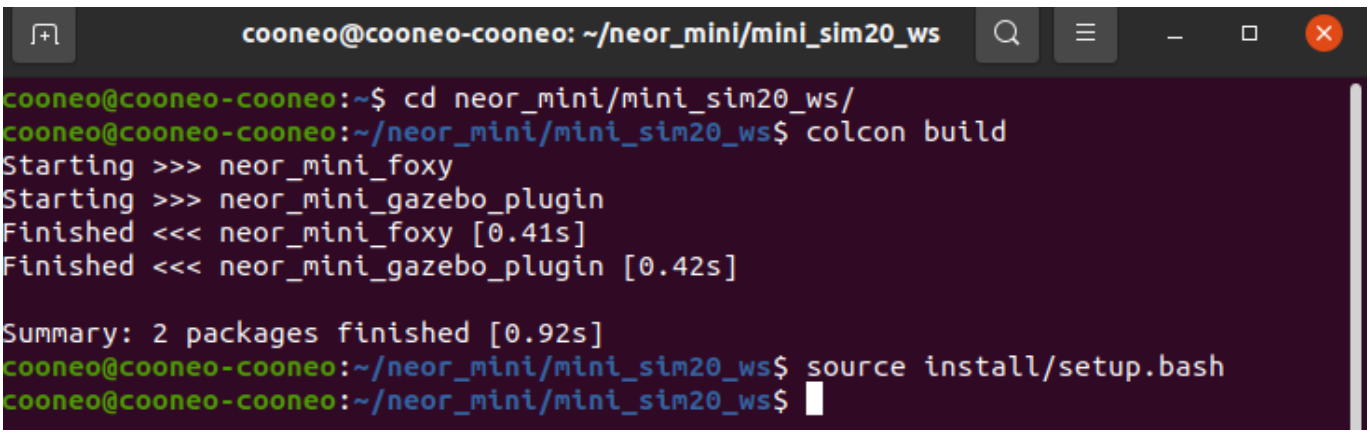
gazebo11

rviz2

chapter 1 : load neor_mini urdf file into rviz by ROS2 - foxy

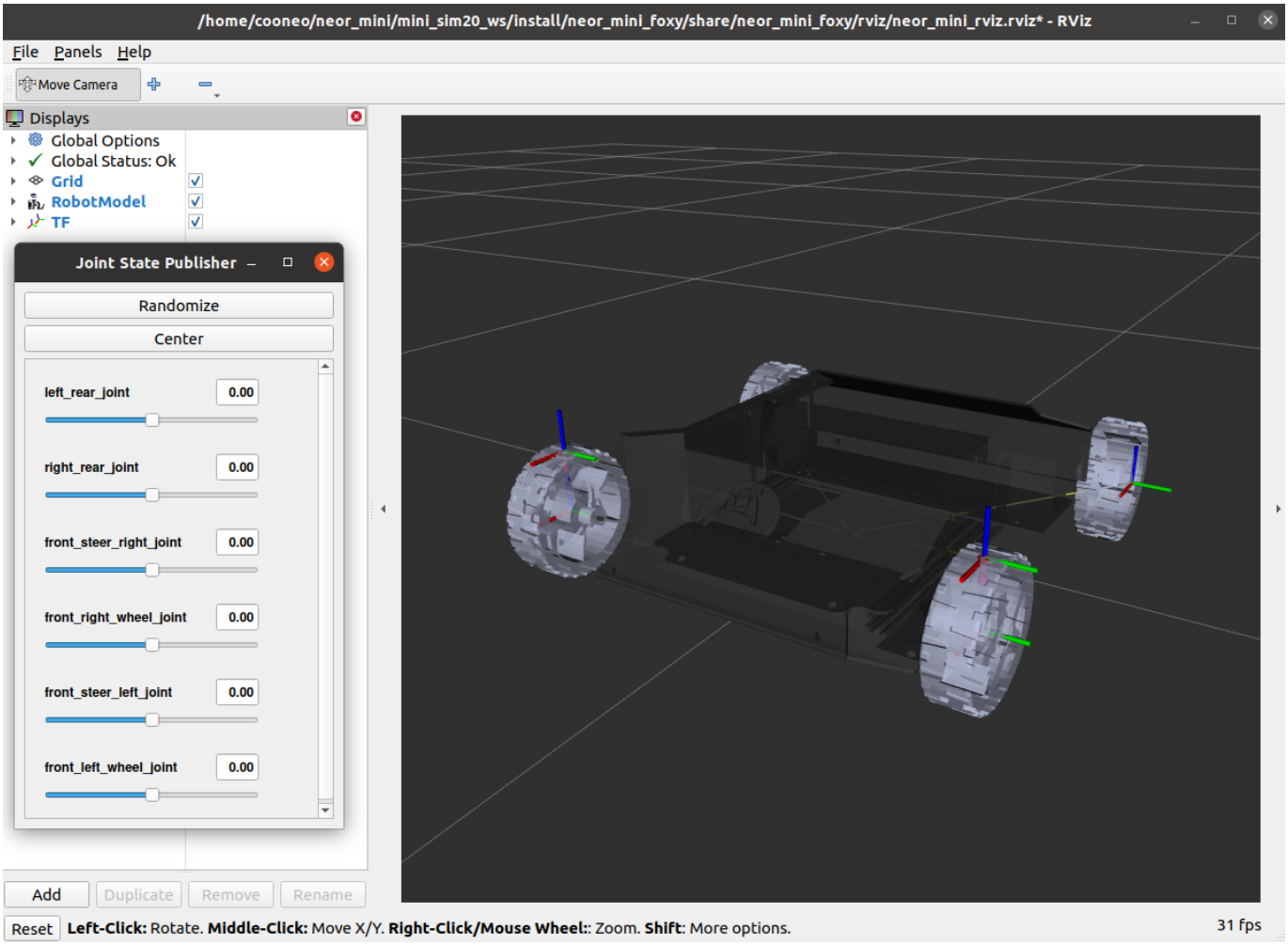
Step 1 : down load code && compile its.

```
# open a new Terminal
git clone -b foxy https://github.com/cooneo/neor_mini.git


# after download neor_mini_foxy project.
cd neor_mini/mini_sim20_ws

# auto install dependence packages by packages.xml file or one by one by your hand
rosdep install -i --from-path src --rosdistro foxy -y

# compile ROS packages
colcon build

# wait a moment && source ROS workspace
source install/setup.bash
```



Step 2 : launch file && load neor_mini urdf into rviz2

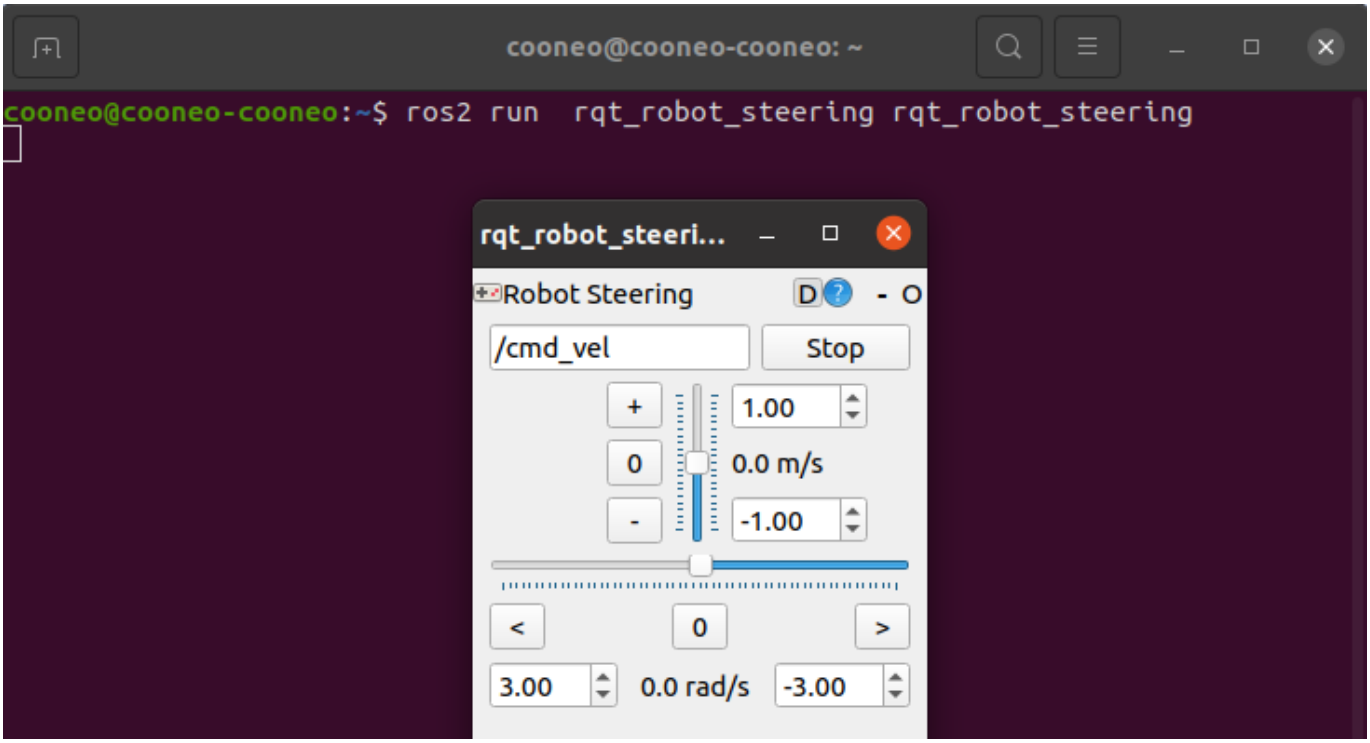
```
# Terminal same as up
ros2 launch neor_mini_foxy display.launch.py
```



chapter 2 : load neor_mini urdf file into gazebo11 && drive it by topics

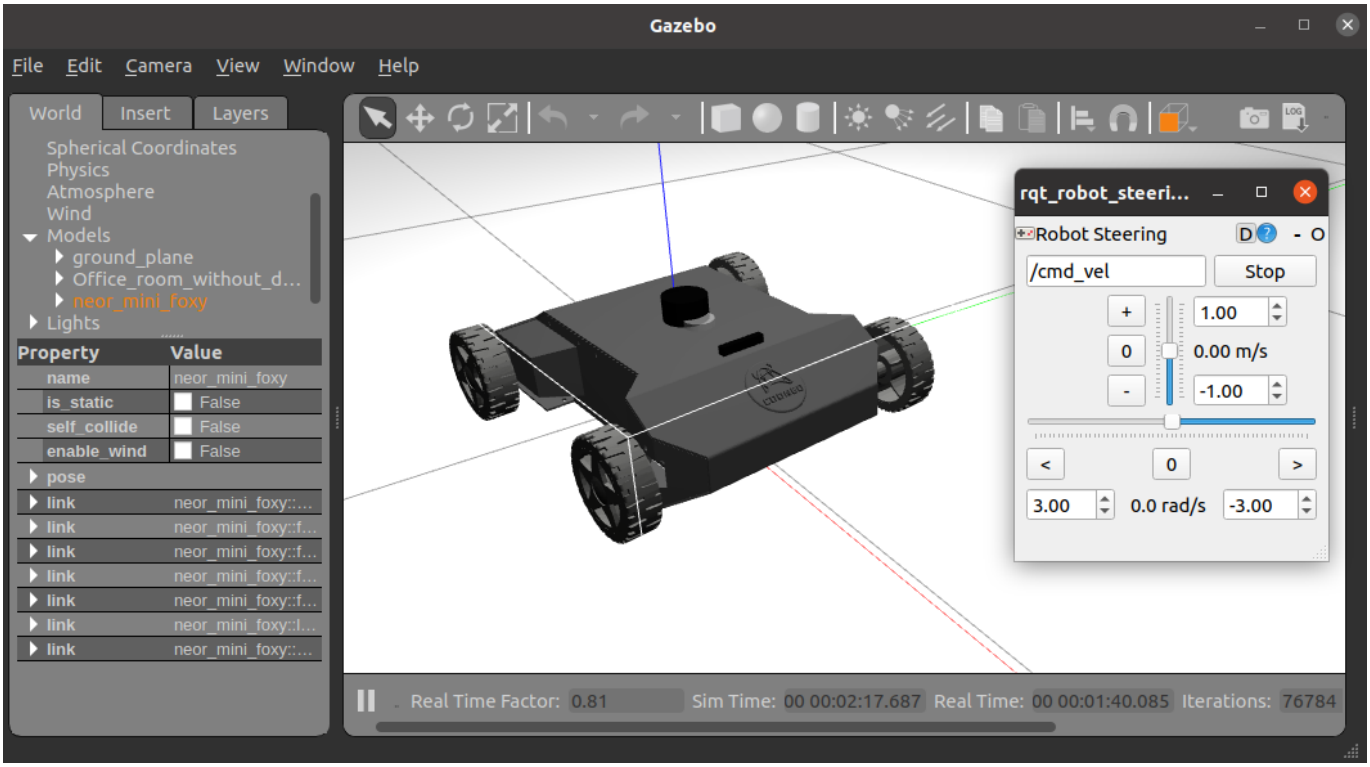
Step 1 : launch rqt_robot_steering ROS node

```
# open a new terminal
ros2 run  rqt_robot_steering rqt_robot_steering
```



Step 2 : launch file && load neor_mini into gazebo11 and drive it.

```
# open a new terminal
cd neor_mini/mini_sim20_ws
colcon build
source install/setup.bash

# launch file
ros2 launch neor_mini_foxy neor_mini_gazebo.launch.py
```


Gazebo
File Edit Camera View Window Help
World Insert Layers
Spherical Coordinates
Physics
Atmosphere
Wind
Models
ground_plane
Office_room_without_d...
neor_mini_foxy
Lights
Property Value
name neor_mini_foxy
is_static False
self_collide False
enable_wind False
pose
link neor_mini_foxy::...
link neor_mini_foxy::f...
link neor_mini_foxy::f...
link neor_mini_foxy::f...
link neor_mini_foxy::f...
link neor_mini_foxy::l...
link neor_mini_foxy::...
rqt_robot_steeri...
Robot Steering
/cmd_vel
Stop
+
1.00
0
0.00 m/s
-
-1.00
<
0
>
3.00
0.0 rad/s
-3.00
Real Time Factor: 0.81
Sim Time: 00 00:02:17.687
Real Time: 00 00:01:40.085
Iterations: 76784