

# ROS2

## Environment

~/ik\_ws

```
cd ik_ws
colcon build
```

## Run

```
source ~/ik_ws/install/setup.bash
ros2 run airship_ik ik_node
```

## Service

Service `/grasp` `grasp_interface_pkg/srv/Grasp`, `Grasp`

```
float64 x
float64 y
float64 z
int8 ret
int8 g
---
int8 ret
```

`x, y, z` are the position of the base

- 1. `g=1` means the robot will grasp the object, `ret=0` means the robot will not grasp the object
  - 2. `g=-1` means the robot will not grasp the object, `ret=1` means the robot will not grasp the object
- `x, y, z` are the position of the base, `ret=1` means the robot will not grasp the object

## Example

```
source ~/ik_ws/install/setup.bash
ros2 service call /grasp grasp_interface_pkg/srv/Grasp "x: 0.3 y: 0.0 z: 0.2 ret: 0 g: 1"
```