**Show different command:**

rospack -h

rosversion -d

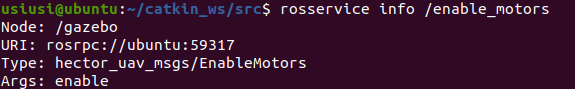
rostopic list

rostopic echo / cmd\_vel

rosnode list

rosmsg list

rosservice list



rosservice call /enable\_motors "enable: true"

rospack list (per guardare tutti i pacchetti installati)

In python puoi usare i pacchetti di python o quelli di ros, ad esempio puoi fare:

import numpy as np

oppure

from geometry\_msgs.msg import Twist, Quaternion

il primo import è dai pacchetti python il secondo dai pacchetti di ros

rospack find turtlesim (per verificare se un pacchetto è installato)

Note: to install could be important remove devel and build folder in catkin folder.

To see all topic currently activated:

rostopic list

rostopic info /cmd\_vel

http://wiki.ros.org/it/ROS/Tutorials/UnderstandingTopics

**To install a package**:

https://industrial-training-master.readthedocs.io/en/melodic/\_source/session1/Installing-Existing-Packages.html

**To install a package of a specific branch**

git clone https://github.com/tu-darmstadt-ros-pkg/hector\_quadrotor.git --branch catkin

**To remove a package**:

Type sudo apt-get remove ros-fuerte-package\_name in the terminal if you have installed a Debian package. Delete the folder otherwise.

**Give permission current folder**:

chmod -R 777 ./

**Build projects and restart**:

catkin build

re.

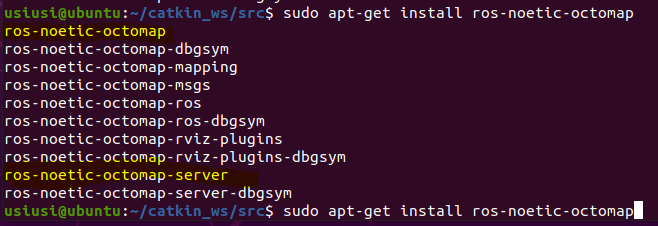
Start always this command in a terminal when run a project (it’s not necessary if open gazebo):

roscore

To install <https://github.com/bingyo/tello_ros_gazebo>



inoltre installare quelli sottolineati in giallo:







HOW TO START tello\_ros\_gazebo

**SET THE WEBCAM:**

In VirtualBox:

Devices -> Webcams

**FROM TERMINAL 1 (in catkin\_ws/src folder)**:

*Activate wireframe mode: View->Wireframe*

source /home/usiusi/catkin\_ws/devel/setup.bash

roslaunch tello\_driver indoor\_slam\_gazebo.launch

**FROM TERMINAL 2**:

source /home/usiusi/catkin\_ws/devel/setup.bash

roslaunch tello\_driver task1.launch

**FROM TERMINAL (OPTIONAL)**:

source /home/usiusi/catkin\_ws/devel/setup.bash

rosservice call /enable\_motors "enable: true"

<https://github.com/ros-teleop/teleop_twist_keyboard>

rosrun teleop\_twist\_keyboard teleop\_twist\_keyboard.py \_repeat\_rate:=10.0

the last code it’s important to have the drone always up (so in the air)

**FROM TERMINAL (OPTIONAL):**

source /home/usiusi/catkin\_ws/devel/setup.bash

rostopic pub -r 10 /cmd\_vel geometry\_msgs/Twist '{linear: {x: 0.1, y: 0.0, z: 0.0}, angular: {x: 0.0,y: 0.0,z: 0.0}}'

**FROM TERMINAL (OPTIONAL):**

source /home/usiusi/catkin\_ws/devel/setup.bash

To see values that are sent

rostopic echo /cmd\_vel

se ti dà una RLException:

source /home/usiusi/catkin\_ws/devel/setup.bash

To install <https://github.com/clydemcqueen/tello_ros>

<https://github.com/TIERS/tello-ros2-gazebo>

