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Task 10:

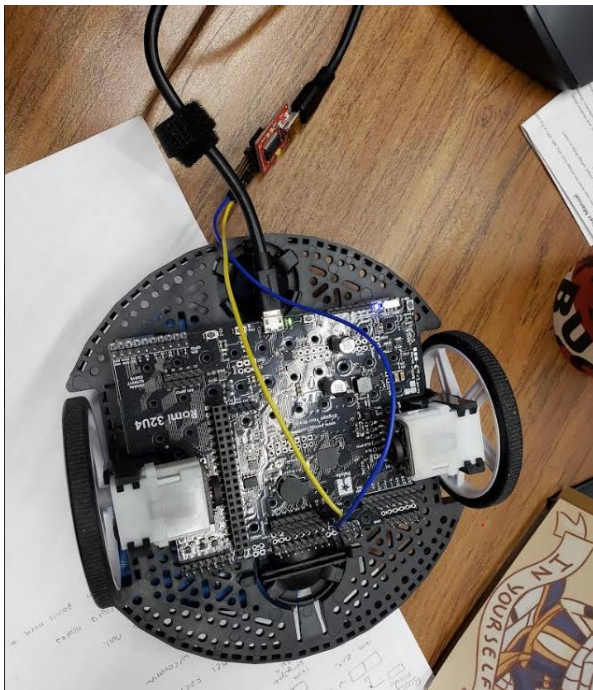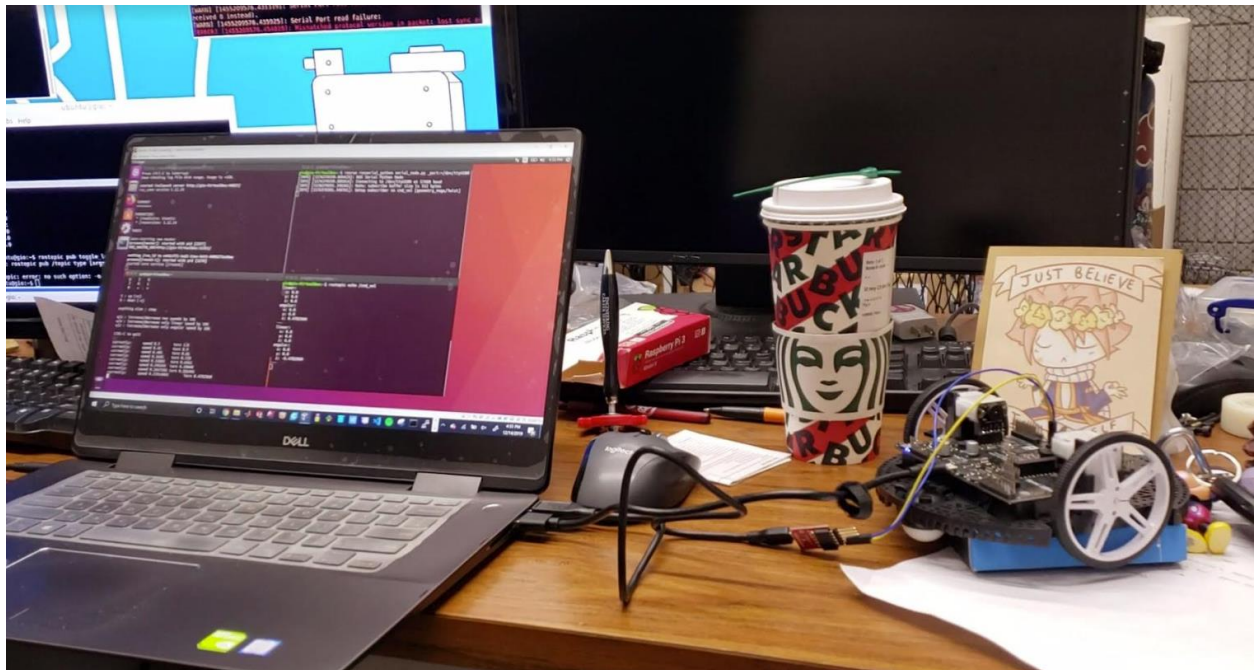Control Rover using Teleop Commands

Video:

https://www.youtube.com/watch?v=dqVmhy_WNGQ

Steps:

1.) Make sure to have the latest Arduino Software installed with respected libraries and drivers installed for the Romi32U4
2.) Download the "Romi-pi Master" code from git hub
3.) Load it onto the board, make sure preferences, board, and port are correct. We had to use a FTDI.
4.) Open four terminals on ROS
   a. Terminal 1: Run roscore
   b. Terminal 2: rosrun rosserial_python serial_node.py _port:=/dev/ttyUSB0
   c. Terminal 3: rosrun teleop_twist_keyboard teleop_twist_keyboard.py
   d. Terminal 4: rostopic echo /cmd_vel
5.) After commands have been pressed. You can run the rover left, right, forward, backward, and stop it using keyboard commands.

Setup:

Commands: