

无人船控制命令总结

- 控制速度
 - 网线连接
 - 修改本机ip地址为 192.168.1.x (x=0~255, x!=230)
 - ping 192.168.1.230 测试是否连上
 - cd python_ws
 - python3 pose.py
- gps
 - 两个电源 12v 1 imu 1gps
 - 1串口 连接电脑
 - ls /dev/tty tab tab 查看串口名 (通常是USB0或者USB1)
 - sudo chmod 666 /dev/串口名
 - roscore
 - source ~/catkin_ws/devel/setup.bash
 - rosrn unionstrong_driver nmea_serial_driver _port:/dev/ttyUSB0 _baud:=115200
 - cutecom 串口界面
 - rostopic list
 - rostopic echo /unionstrong/gpfpd 命令行中显示gps数据信息
- 激光雷达
 - 修改网络配置

Editing Wired connection 1

Connection name:

General | Ethernet | 802.1x Security | DCB | IPv4 Settings | IPv6 Settings

Method:

Addresses

Address	Netmask	Gateway
192.168.1.110	24	192.168.1.201

DNS servers:

Search domains:

DHCP client ID:

☐ Require IPv4 addressing for this connection to complete

- roscore
 - source catkin_velodyne/devel/setup.bash
 - roslaunch src/./velodyne_pointcloud/launch/VLP_16xx.launch
- rviz 可视化
 - map 改为 velodyne
 - add pointcloud
- rosbag record -a 记录
- rosbag play xxx 重放