

Running Gazebo

Install gazebo:

```
sudo apt-get install ros-%kinetic%-simulator-gazebo
```

Setup:

```
source ~/catkin_ws/devel/setup.bash
```

This launches gazebo:

```
roslaunch gazebo_ros empty_world.launch
```

Spawn urdf with the following where “object.urdf” is the name of your urdf and “1” is the height at which the model is spawned (m).

```
roslaunch gazebo spawn_model -file `pwd`/object.urdf -urdf -z 1 -model my_object
```

urdf in RViz

This assumes that you have an existing urdf file complete with launch packages etc, else see here to create a model from scratch:

<http://wiki.ros.org/urdf/Tutorials/Building%20a%20Visual%20Robot%20Model%20with%20URDF%20from%20Scratch>

Or here for a SolidWorks exporter: http://wiki.ros.org/sw_urdf_exporter

To open the file in RViz, enter the following where “simpleModel” is the package name and “simpleModel.urdf” is the name of the file:

```
roslaunch simpleModel urdf.visualize.launch model:=$(find simpleModel)/urdf/simpleModel.urdf'
```