

PS4: Rviz & Gazebo

Steps to run:

- 1) First terminal: `roscd, catkin_make, roscore`
- 2) Second terminal: `roslaunch ps4_kvc2 ps4_kvc2.launch`

In this assignment, an existing 1DOF robot description was modified to become a 2DOF robot by adding 1 link and 1 joint. The `minimal_joint_controller` node was modified as well, in order to control the new joint, and a modified version of the `minimal_robot.launch` file is used to automatically open rviz and Gazebo, load the robot model, and activate the joint controller node to control the robot.

Two screencasts are included in this file: a shorter version that shows only the robot's motion, and a longer version that also shows tests: placing objects in Gazebo and checking `rqt_plot`.