**PRIMITIVE SHAPE DESIGNING BOT USING ROS**

**GROUP – 11**

**REFERENCES:**

* <https://www.youtube.com/watch?v=H9XcE1vDX1Q>

By the above reference, we connected the GPIO pins from raspberry pi 3 to the motor drive pins. We established a connection between them as output and input.

* <https://www.youtube.com/watch?v=uW8YVcBjPGU>

In this reference, we built the robot chassis kit and we arranged the motors in a proper way such that it’s easy to connect to the motor driver. We also gave the power to motor driver and a correct wheel alignment.

* <https://www.raspberrypi.com/software/>

We came to know od raspberry pi 3 and it’s implementations. It has certain amount of GPIO, Power and ground pins.

* <https://roboticsbackend.com/using-ros-on-raspberry-pi-best-practices/>

These are some basic practices of the ros and raspberry pi connections. We used this data to connect the ubuntu with the raspberry pi.

* <https://www.chiark.greenend.org.uk/~sgtatham/putty/latest.html>

We used putty terminal to run the commands. So, we installed it and it’s easy to function.

**GIT HUB PROJECT LINK:**

* [**https://github.com/KEERTHITEJ007/Primitive-Shape-Designing-bot-using-ROS**](https://github.com/KEERTHITEJ007/Primitive-Shape-Designing-bot-using-ROS)