

ROS noetic :

- Setup your sources.list:

```
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu $(lsb_release -sc) main" >
/etc/apt/sources.list.d/ros-latest.list'
```

- Set up your keys:

```
sudo apt install curl # if you haven't already installed curl
```

```
curl -s https://raw.githubusercontent.com/ros/rosdistro/master/ros.asc | sudo apt-key add -
```

- package index is up-to-date:

```
sudo apt update
```

- Installation:

```
sudo apt install ros-noetic-desktop-full
```

- Environment setup:

```
source /opt/ros/noetic/setup.bash
```

```
echo "source /opt/ros/noetic/setup.bash" >> ~/.bashrc
```

```
source ~/.bashrc
```

- Dependencies for building packages:

```
sudo apt install python3-rosdep python3-rosinstall python3-rosinstall-generator python3-wstool build-essential
```

```
sudo apt install python3-rosdep
```

```
sudo rosdep init
```

```
rosdep update
```

Rtabmap:

- Installation:
`sudo apt install ros-noetic-rtabmap-ros`

Realsense SDK 安装:

- Key:
`sudo apt-key adv --keyserver keyserver.ubuntu.com --recv-key F6E65AC044F831AC80A06380C8B3A55A6F3EFCDE || sudo apt-key adv --keyserver hkp://keyserver.ubuntu.com:80 --recv-key F6E65AC044F831AC80A06380C8B3A55A6F3EFCDE`
- Add server :
`sudo add-apt-repository "deb https://librealsense.intel.com/Debian/apt-repo $(lsb_release -cs) main" -u`
- 安装库:
`sudo apt-get install librealsense2-dkms librealsense2-utils librealsense2-dev librealsense2-dbg`
- Run:
`realsense-viewer`