

ROS Interface for P‑Rob

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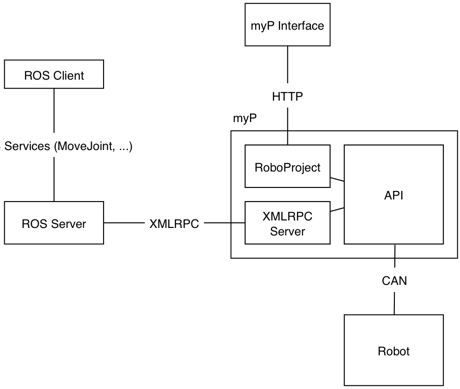
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# Concept

A ROS Service can be called from any ROS client, a test example is included in the package. The ROS Server communicates through XMLRPC to the myP API, which includes all necessary functions. To add new ROS services, only the ROS Server has to be extended.



# Installing ROS

1. Install ROS Indigo: <http://wiki.ros.org/ROS/Installation>
2. Create a catkin workspace
3. Copy the F&P package “prob\_ros\_interface” to the workspace
4. Compile the code and source your setup
   1. $ catkin\_make
   2. $ source devel/setup.bash
5. run roscore
6. Now you are ready to run the example program

# Example Program

Requirements:

* ROS Indigo has to be installed and roscore running
* prob\_ros\_interface is installed
* XMLRPC Server needs to be running on P-Rob (xmlrpc\_server.py)

Start the server with the IP address of the robot:

$ rosrun prob\_interface prob\_server.py 192.168.21.157

Run the sample demo to move joint 1 of P-Rob by 10 degrees and back again:

$ rosrun prob\_interface client\_demo.py 1 10

$ rosrun prob\_interface client\_demo.py 1 0