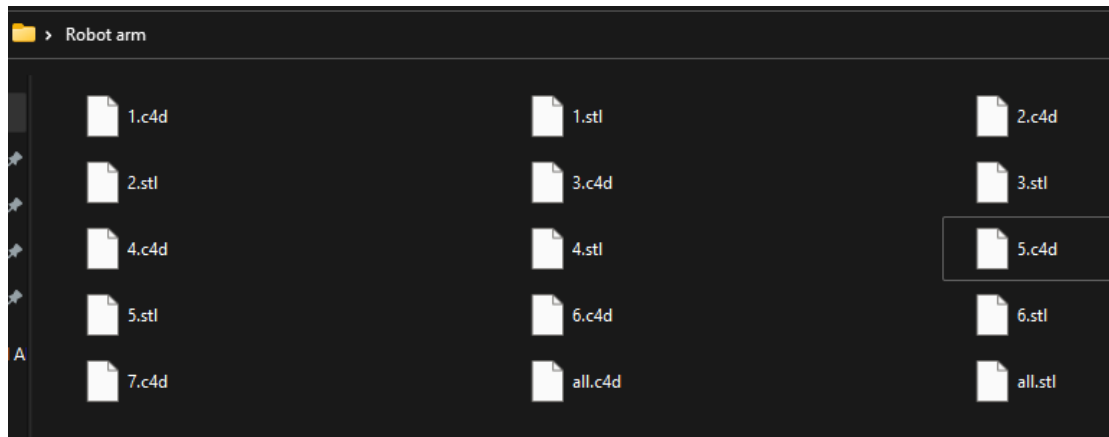


Creating-ROS-Package

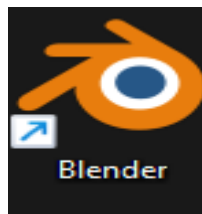
1- Download stl files:

This is the link to download stl files:

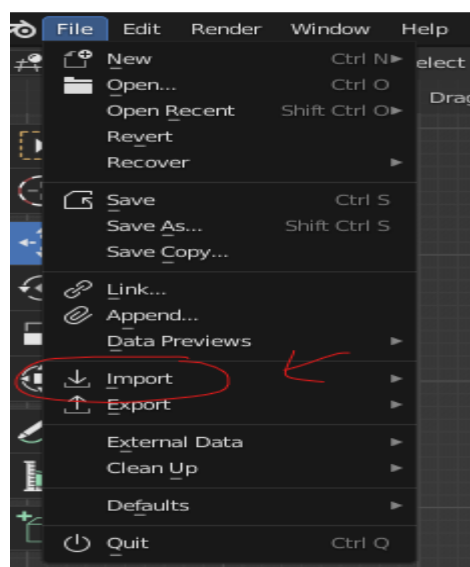
<https://drive.google.com/drive/folders/18E0vgwkuOhObBcaOVkfFNj-FnycijkbE>



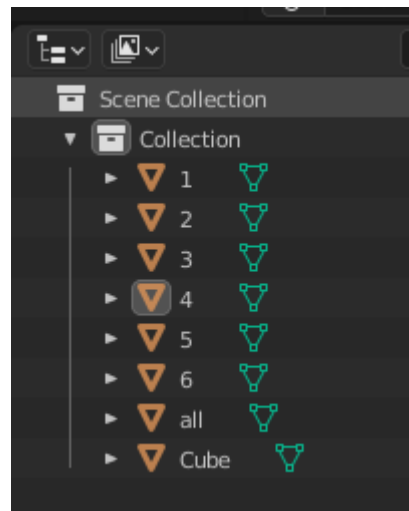
2- Download and use "blender program:



In this step you need to import all stl files to blender



After import stl files you see they're in your program



link to download blender: <https://www.blender.org/>

3- Export the project as "URDF" file and make joint:

this link: <https://www.youtube.com/watch?v=CrMvtlZl3LI>

4-Creating a ROS Package:

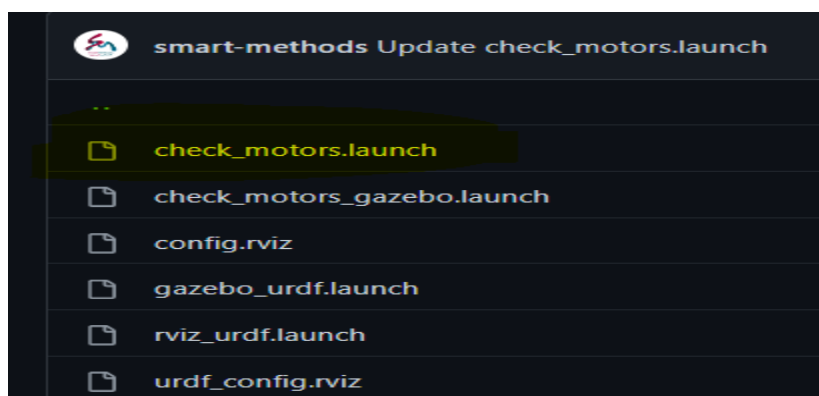
To do that follow all steps in this link:

<http://wiki.ros.org/ROS/Tutorials/CreatingPackage>

5- Run the urdf and move the robot:

PATH: `~\robot_arm\robot_arm_pkg\launch`

Open the check_motors. Launch



Change the textfile to the new "urdf" you made it before

```
17 lines (13 sloc) 848 Bytes
1 <?xml version="1.0"?>
2 <launch>
3 <!-- upload urdf -->
4 <param name="robot_description" textfile="$(find robot_arm_pkg)/urdf/arduino_robot_arm.urdf" />
5
6 <!-- Combine joint values -->
7 <node name="robot_state_publisher" pkg="robot_state_publisher" type="robot_state_publisher"/>
8
9 <!-- Show in Rviz -->
10 <node name="rviz" pkg="rviz" type="rviz" args="-d $(find robot_arm_pkg)/launch/config.rviz" />
11
12 <!-- send joint values -->
13 <arg name="use_gui" default="true" doc="Should the joint_state_publisher use a GUI for controlling joint states" />
14 <node pkg="joint_state_publisher" type="joint_state_publisher" name="joint_state_publisher" output="screen" unless="$(arg use_gui)" />
15 <node pkg="joint_state_publisher_gui" type="joint_state_publisher_gui" name="joint_state_publisher_gui" output="screen" if="$(arg use_gui)" />
16
17 </launch>
```

6- Finally:

