ifconfig(查詢IP地址)

roslaunch open\_manipulator\_controller open\_manipulator\_controller.launch usb\_port:=/dev/ttyUSB2(啟動機器臂)

ls /dev/ttyUSB\*(顯示未命名US B的數量)

roslaunch open\_manipulator\_control\_gui open\_manipulator\_control\_gui.launch(打開機器臂的資訊頁面)

roslaunch open\_manipulator

rostopic list

rosservice list 和robot溝通的一方法

rosservice info /goal\_tool\_control

rostopic info (topic名字)

rosmsg show (topic類型)

roslaunch robot\_vision\_openvino openpose\_ros.launch(讀取人體支架)

roslaunch astra\_camera astra.launch(開啟鏡頭)

rostopic echo /yolo\_ros/bounding\_boxes

roslaunch robot\_vision\_openvino yolo\_ros.launch(讀取方框中的物品類型)

ls(列出檔案清單)

cd(改變目錄)

ls -a(列出包括隱藏檔案的所有檔案)

開始所需的指令

roslaunch astra\_camera astra.launch

roslaunch open\_manipulator\_controller open\_manipulator\_controller.launch usb\_port:=/dev/ttyUSB2

roslaunch lingao\_navigation navigate.launch map\_file:=/home/mustar/maps/fablab.yaml

roslaunch lingao\_bringup robot.launch

roslaunch mr\_voice voice.launch

尋找import路徑:

1.通過rostopic list 尋找需要import 的topic 名字

2.通過rostopic info 尋找rostopic類型

補充：

·rostmsg show找到topic内的參數

VM版開啟地圖

roslaunch turtlebot\_gazebo turtlebot\_world.launch world\_file:=/home/mustar/catkin\_ws/worlds/Jupiter\_Robot\_Office.world

VM版開啟rviz

roslaunch turtlebot\_rviz\_launchers view\_navigation.launch

roslaunch turtlebot\_gazebo amcl\_demo.launch map\_file:=/home/mustar/catkin\_ws/maps/JupiterOfficeSim.yaml