Step by step installation guide

1: Install Ubuntu 14.04. Please don't install Ubuntu in your VMware or other virtual machines.

2: Install ROS indigo, please follow the steps here: http://wiki.ros.org/indigo/Installation/Ubuntu.

3: Create a new ROS workspace for fetch:

mkdir fetch_ros_workspace/src -p
cd fetch_ros_workspace/src/
catkin_init_workspace

4: Download fetch ROS code from Github, and put them in the "fetch_ros_workspace/src/" directory.

git clone https://github.com/fetchrobotics/fetch_ros
cd ..
 # install some dependent packages
sudo apt-get install ros-indigo-opencv-candidate ros-indigo-costmap-2d ros-indigo-moveit-full

catkin_make
source devel/setup.bash

5: Install gazebo simulator

sudo apt-get install ros-indigo-fetch-gazebo-demo

6: launch the simulator

roslaunch fetch_gazebo simulation.launch

It will be a long time (about 5 min depends on your network) to start the gazebo for the first time, as it downloads the model from internet.

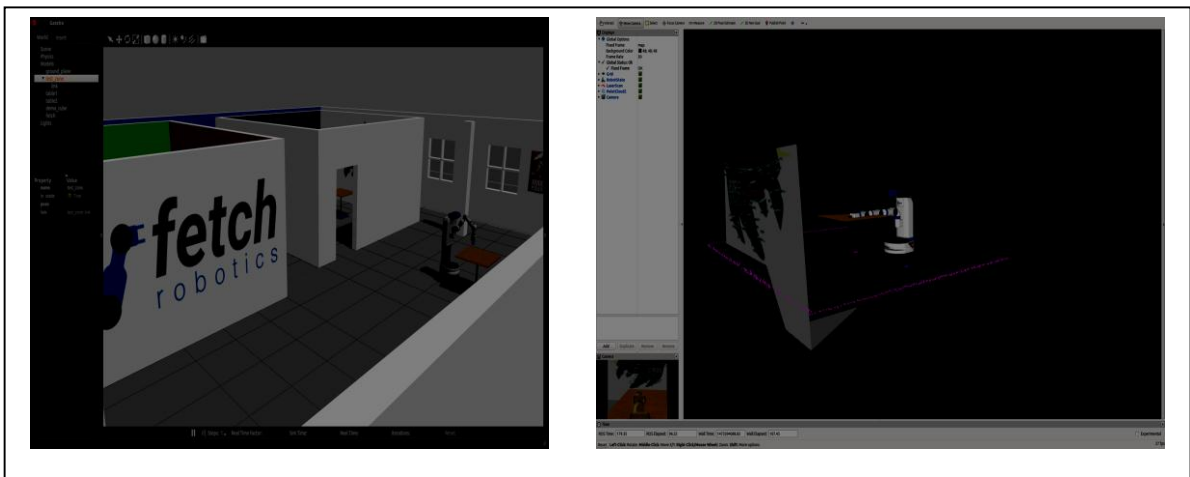7: check the data

roslaunch fetch_gazebo playground.launch
open another terminal
roslaunch fetch_gazebo_demo demo.launch
start rviz and add the depth/image/baselaser to your rviz.
Rviz

Now you can see the RGB image, depth scan and the laser scan.(Black

background: my screen capture software works not well on the OpenGL rendering, but you can see the data as well.)

If you want to know more about the fetch robot, please refer to the website: http://docs.fetchrobotics.com/introduction.html.