1   Installation

1. Install the joint state publisher:

```
$ sudo apt install
      ros-melodic-joint-state-publisher-gui
```

2. Next, git clone realsense package into your catkin folder and run catk-
   inmake.

```
$ git clone
      https://github.com/pal-robotics/realsense_gazebo_plugin.git
```

2   Package Overview

2.1   urdf

The urdf folder is used to store (.urdf.xacro) and (.gazebo.xacro) files. (.urdf.xacro)
files describe the transformations between the various links of the robot,
along with other variables such as intertia.
(.gazebo.xacro) files would describe the kinematic properties of the robot
such as velocity limits, coefficient of friction etc.