

## Getting started Manual InMoov ROS Project

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## **Introduction:**

This Project includes three major pieces of software. The intended operating system is Ubuntu 16.04 LTS newer versions probably work just fine but 16.04 is the official version ROS Kinetic Kame is supported on. We chose a slightly different version Kubuntu 16.04 LTS . . Also we use the version of MoveIt matching to ROS Kinetic Kame which needs to be installed for the simulation and motion planning involved.

## **Kubuntu 16.04 LTS**

### ***Installation***

The current setup runs on Kubuntu 16.04 LTS as it is the primary target for ROS Kinetic. Kubuntu needs to be installed first here are some manuals to do this.

-Installation Manual (en):

<https://userbase.kde.org/index.php?title=Kubuntu/Installation&oldid=356826>

-Installation Manual (de):

[https://wiki.ubuntuusers.de/Kubuntu\\_Installation/](https://wiki.ubuntuusers.de/Kubuntu_Installation/)

## **ROS Kinetic Kame**

### ***Installation***

The InMoov ROS Project currently runs on ROS Kinetic Kame which comes with very good documentation and an installation manual. <http://wiki.ros.org/kinetic/Installation/Ubuntu>

### ***Getting Started***

ROS is a elegant system for controlling robots but it has various mechanisms and ideas which need to be understood in order to efficiently use it. Therefore it is a good idea to play around with some or all of the tutorials at this point. <http://wiki.ros.org/ROS/Tutorials>

## **MoveIt**

### ***Installation***

Motion Planning, Collision checking and Simulation is done using MoveIt we need to install this after ROS. Make sure you chose the correct version corresponding to ROS Kinetic Kame <http://moveit.ros.org/install/>

### ***Getting Started***

MoveIt also Provides some good Tutorials which can be found here: [http://docs.ros.org/kinetic/api/moveit\\_tutorials/html/index.html](http://docs.ros.org/kinetic/api/moveit_tutorials/html/index.html)

# InMoov

## Installation of some packages needed for InMoov

After Installing Kubuntu and ROS it is necessary to install a few extra packages which might not be included in the main installation. Here is a command to do just this.

```
sudo apt-get install arduino dkms qt5-default qtcreator clang-format-3.8 ros-kinetic-desktop-full ros-kinetic-rqt ros-kinetic-rqt-common-plugins ros-kinetic-moveit ros-kinetic-rosserial-arduino ros-kinetic-rosserial ros-kinetic-xacro ros-kinetic-opencv3 ros-kinetic-cv-bridge ros-kinetic-compressed-depth-image-transport ros-kinetic-compressed-image-transport ros-kinetic-usb-cam ros-kinetic-pyros ros-kinetic-trac-ik liburdfdom-tools python-wstool python-catkin-tools python-pip
```

Next Step we need to install a Python Package:

```
sudo pip install qdarkstyle
```

## Setup

The first step is to setup a new catkin workspace.

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

After completing this copy the xenial\_kinetic branch of InMoov ROS packages into the src folder you just created. These packages can be found here:

[https://github.com/TheOnlyRoxion/inmoov\\_ros/tree/xenial\\_kinetic](https://github.com/TheOnlyRoxion/inmoov_ros/tree/xenial_kinetic)

The Next step is to navigate in a Terminal to your catkin workspace and run the Commands „catkin\_make“ to build all packages and „. devel/setup.bash“ to let ROS know about all of your new ROS packages.

To check if everything went smoothly run the following commands in Terminal:

- start roscore = `roscore`
- open a new Terminal and run = `roslaunch inmoov_description demo.launch`

Now RViz and a Joint\_state\_publisher UI should start.

After everything is started you should be able to use Joint\_state\_publisher to move the robot.

## MoveIt

The Model used for Simulation in the InMoov packages should be properly setup.

Should the need arise to modify InMoov's model inmoov\_description contains those folders. The movit folder contains the setup\_assistant. You can launch this in Terminal using “roslaunch inmoov\_description setup\_assistant.launch” which also comes with a handy Tutorial.

[http://docs.ros.org/kinetic/api/moveit\\_tutorials/html/doc/setup\\_assistant/setup\\_assistant\\_tutorial.html](http://docs.ros.org/kinetic/api/moveit_tutorials/html/doc/setup_assistant/setup_assistant_tutorial.html)

For some changes e.g. joint limits or kinematics it might be more useful to change those values directly in the corresponding file. You can find those under /inmoov\_description/moveit/config .

## **Arduino**

In order to use Arduino we need to setup a few things Start at 2.2.

[http://wiki.ros.org/rosterial\\_arduino/Tutorials/Arduino IDE Setup](http://wiki.ros.org/rosterial_arduino/Tutorials/Arduino%20IDE%20Setup)

## **Msg Srv**

If changing or adding new messages or services, add them to Arduino libraries follow this manual.

[http://wiki.ros.org/rosterial/Tutorials/Adding Other Messages](http://wiki.ros.org/rosterial/Tutorials/Adding%20Other%20Messages)

## **Further useful links**