

Robot Operating System – uruchomienie robota firmy Universal Robots

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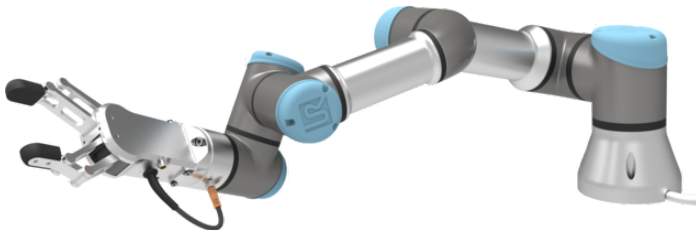


- ROS Master:

```
$ roscore
```



Sterowniki producenta

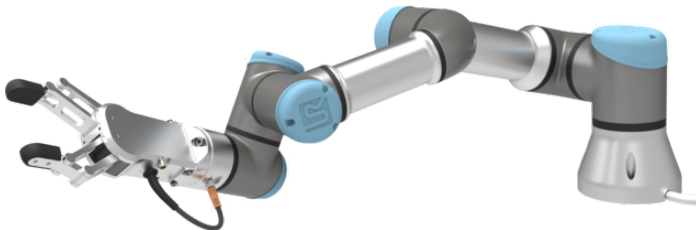


```
$ cd ~/catkin_ws/src
```

```
$ git clone https://github.com/ros-industrial/universal_robot
```



Rozszerzony Sterownik

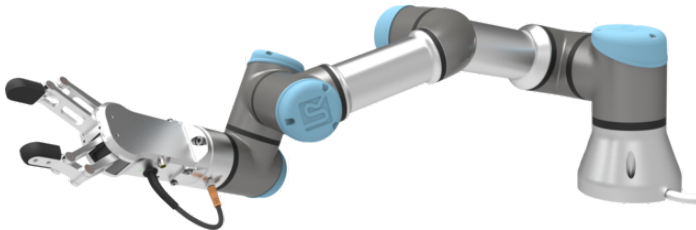


```
$ cd ~/catkin_ws/src
```

```
$ https://github.com/ThomasTimm/ur_modern_driver
```



Rozszerzony Sterownik - patch

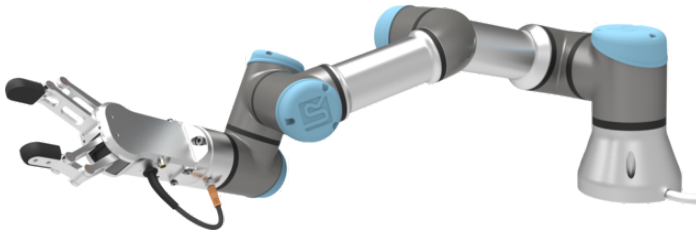


https://github.com/ThomasTimm/ur_modern_driver/issues/58

Zamiana 'controller_it->hardware_interface' na
'controller_it->claimed_resources.at(0).hardware_interface'



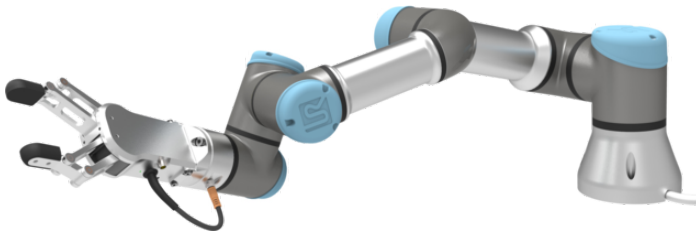
Niezbędne wtyczki do Gazebo i kompilacja



```
$ sudo apt-get install ros-kinetic-gazebo-ros-pkgs ros-kinetic-gazebo-ros-control  
$ cd ~/catkin_ws/src  
$ catkin_make
```



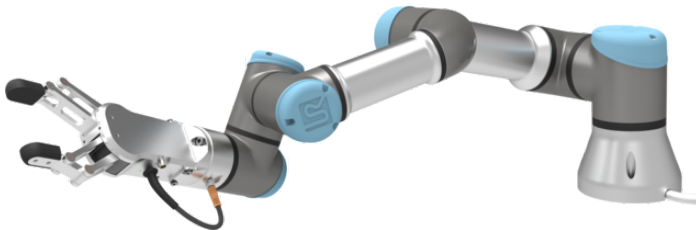
Uruchomienie Gazebo (w nowym terminalu)



```
$ cd ~/catkin_ws/src  
$ source devel/setup.bash  
$ roslaunch ur_gazebo ur3.launch
```



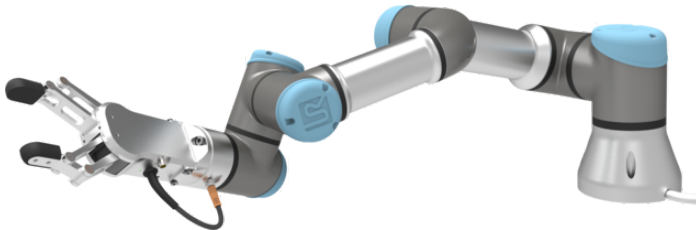
Uruchomienie MoveIt! (w nowym terminalu)



```
$ cd ~/catkin_ws/src  
$ source devel/setup.bash  
$ roslaunch ur3_moveit_config ur3_moveit_planning_execution.launch sim:=true limited:=true
```



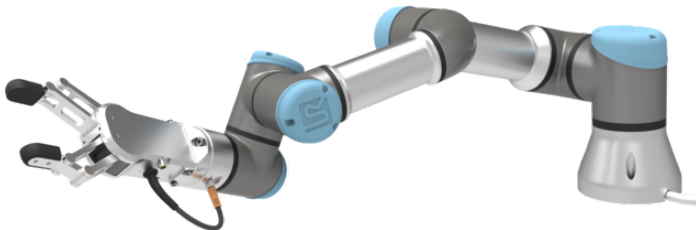
Uruchomienie RViz (w nowym terminalu)



```
$ cd ~/catkin_ws/src  
$ source devel/setup.bash  
$ roslaunch ur3_moveit_config moveit_rviz.launch config:=true
```

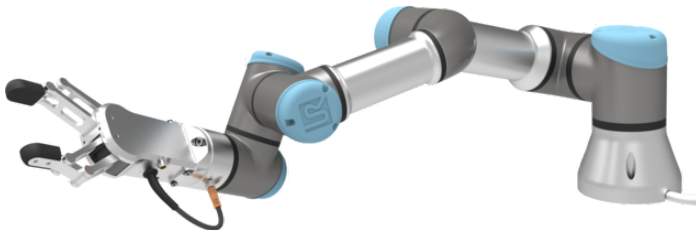


Przykładowy program



```
$ cd ~/catkin_ws/src  
$ git clone https://github.com/dominikbelter/control_ur3sim  
$ roslaunch ur3_moveit_config moveit_rviz.launch config:=true
```





Projekt do pobrania z Github:

```
$ cd ~/catkin_ws/src  
$ git https://github.com/dominikbelter/control_ur3sim  
$ cd ..  
$ catkin_make  
$ rosrn control_ur3sim control_ur3sim
```





irm.put.poznan.pl
www.monoscience.com

