Table of Contents

Lessons learned

- Todo & Advice
- Lessons Learned

Archive

- Previous Groups
- Research Archive
- Skylab Architecture
- Skylab
- Multi master
- WillyWRT
- Realisation
- Hardware
- Brain
- Design Guild
- Social interaction
- Speech
- Speech recognition
- IMU
- Human Detection
- Radeffect App

1. Installation of Ubuntu on Skylab VM;s

The VM’s Fetcher and Sylab ROS master have ROS installed. Run these commands on Ubuntu 16.04 to install ROS Kinetic ready to run.

```
sudo sh -c 'echo "deb http://packages.ros.org/ros/ubuntu $(lsb_release -sc) main" >
/etc/apt/sources.list.d/ros-latest.list'

sudo apt-key adv --keyserver hkp://ha.pool.sks-keyservers.net:80 --recv-key
421C365BD9FF1F717815A3895523BAEEB01FA116

sudo apt-key adv --keyserver hkp://keyserver.ubuntu.com:80 --recv-key
421C365BD9FF1F717815A3895523BAEEB01FA116

sudo apt-get update

sudo apt-get install ros-kinetic-desktop-full

apt-cache search ros-kinetic

sudo rosdep init

rosdep update

echo "source /opt/ros/kinetic/setup.bash" >> ~/.bashrc

source ~/.bashrc

sudo apt-get install python-rosinstall python-rosinstall-generator python-wstool
build-essential

mkdir -p ~/catkin_ws/src

cd ~/catkin_ws/

catkin_make

source devel/setup.bash
```

reference: http://wiki.ros.org/kinetic/Installation/Ubuntu