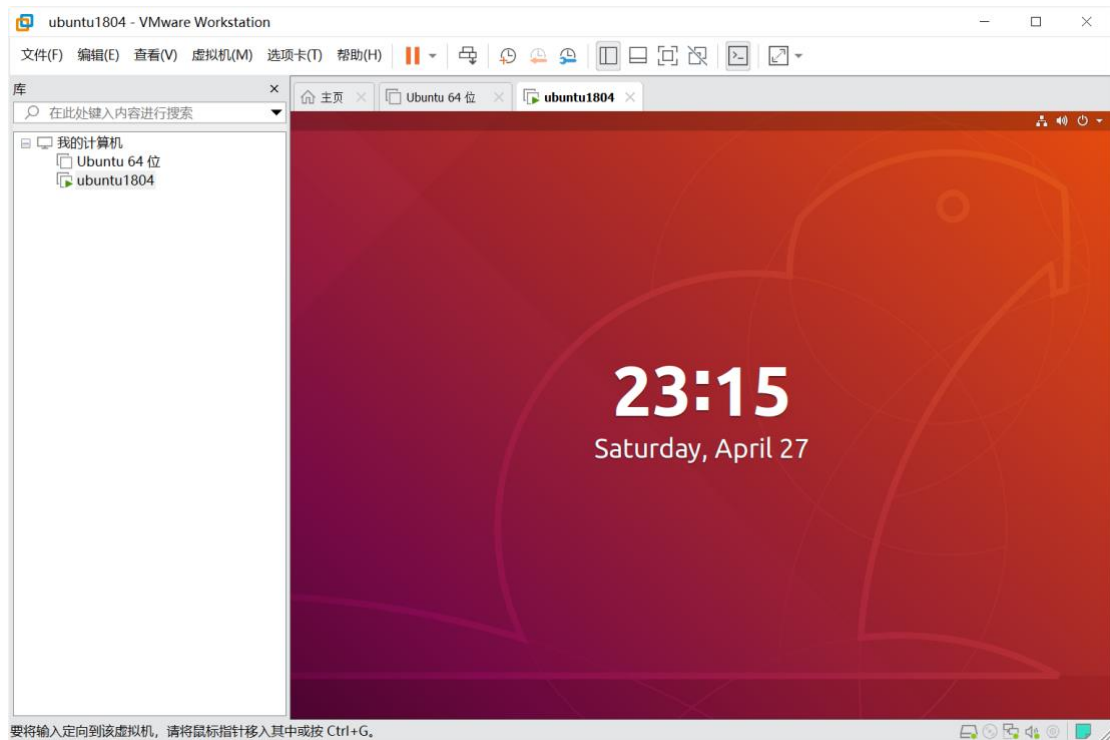
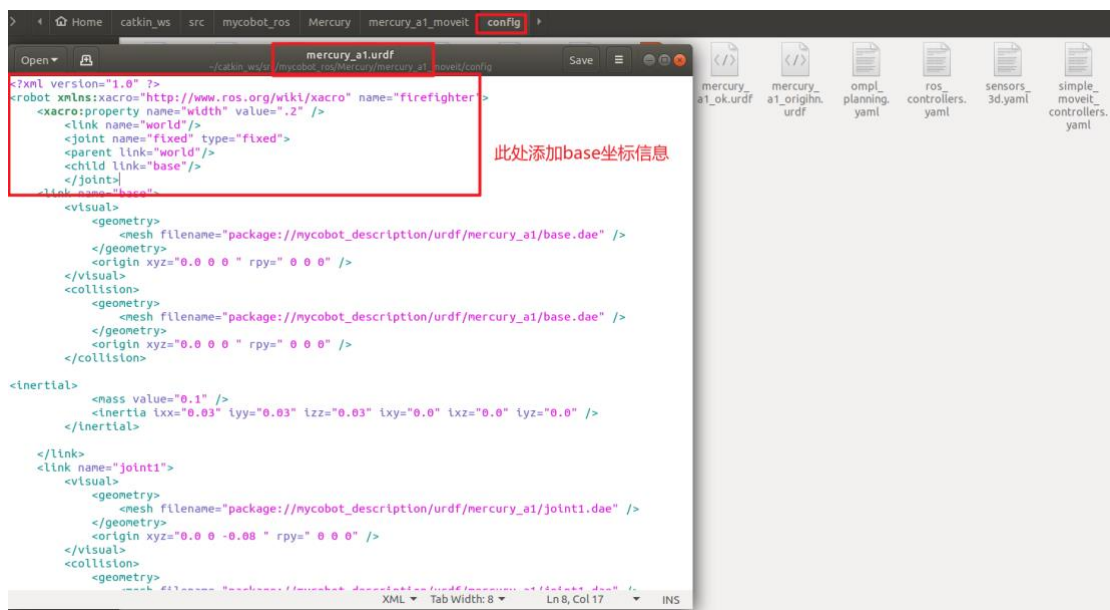


目前电脑中主要有两个环境,其中 ubuntu1804 是 18 的环境,其中 ubuntu64 位是 20.04 的环境,其中目前只在 1804 环境下运行 gazebo 和 ros,, 密码都为 Elephant



为了实现固定操作, 此处修改代码用于固定 base 世界坐标系的标签



项目参考链接:

<https://docs.elephantrobotics.com/docs/gitbook/12-ApplicationBaseROS/12.2-ROS2/12.2.1-ROS2%E7%9A%84%E5%AE%89%E8%A3%85.html>

项目运行的方式:

roslaunch mercury_a1_moveit demo_gazebo.launch

其中 demo.launch 文件是 ros+rviz 的仿真

其中 gazebo.launch 文件是 gazebo 的仿真文件

其中 demo_gazebo.launch 文件是实现两个同步仿真

```
/home/ubuntu1804/catkin_ws/src/mycobot_ros/Mercury/mercury_a1_moveit/launch/demo_gazebo.launch http://localhost:11311
File Edit View Search Terminal Help
[ 77%] Built target mybuddy_communication_generate_messages_cpp
[ 79%] Built target mypalletizer_communication_generate_messages_nodejs
[ 81%] Built target mypalletizer_communication_generate_messages_lisp
[ 83%] Built target mypalletizer_communication_generate_messages_cpp
[ 86%] Built target mypalletizer_communication_generate_messages_eus
[ 88%] Built target ultraarm_communication_generate_messages_eus
[ 91%] Built target ultraarm_communication_generate_messages_py
[ 93%] Built target ultraarm_communication_generate_messages_lisp
[ 96%] Built target ultraarm_communication_generate_messages_cpp
[ 96%] Built target mercury_a1_communication_generate_messages
[100%] Built target ultraarm_communication_generate_messages_nodejs
[100%] Built target myarm_communication_generate_messages
[100%] Built target mycobot_320_communication_generate_messages
[100%] Built target mycobot_communication_generate_messages
[100%] Built target mecharm_communication_generate_messages
[100%] Built target mybuddy_communication_generate_messages
[100%] Built target mypalletizer_communication_generate_messages
[100%] Built target ultraarm_communication_generate_messages
ubuntu1804@ubuntu:~/catkin_ws$ roslaunch mercury_a1_moveit demo_gazebo.launch
RLError: [demo_gazebo.launch] is neither a launch file in package [mercury_a1_moveit] nor is [mercury_a1_moveit] a launch file name
The traceback for the exception was written to the log file
ubuntu1804@ubuntu:~/catkin_ws$ roslaunch mercury_a1_moveit demo.launch
RLError: [demo.launch] is neither a launch file in package [mercury_a1_moveit] nor is [mercury_a1_moveit] a launch file name
The traceback for the exception was written to the log file
ubuntu1804@ubuntu:~/catkin_ws$ export ROS_HOSTNAME=localhost
ubuntu1804@ubuntu:~/catkin_ws$ export ROS_MASTER_URI=http://localhost:11311
ubuntu1804@ubuntu:~/catkin_ws$ source devel/setup.bash
ubuntu1804@ubuntu:~/catkin_ws$ echo $ROS_PACKAGE_PATH
/home/ubuntu1804/catkin_ws/src:/opt/ros/melodic/share
ubuntu1804@ubuntu:~/catkin_ws$ roslaunch mercury_a1_moveit demo_gazebo.launch
... logging to /home/ubuntu1804/.ros/log/88a2c81a-b529-11e7-9303-000c29ce4649/roslaunch-ubuntu-1804.log
Checking log directory for disk usage. This may take a while.
Press Ctrl-C to interrupt
Done checking log file disk usage. Usage is <1GB.

started roslaunch server http://localhost:36455/

SUMMARY
```

操作过程:

选择目标位置 + plan，我们在 rviz 中看见机器完成动作组的规划后，可以使用 execute 命令发送动作组给到 gazebo 进行仿真，便完成了操作。

