ROS2 entity robot dog state acquisition

Quick use

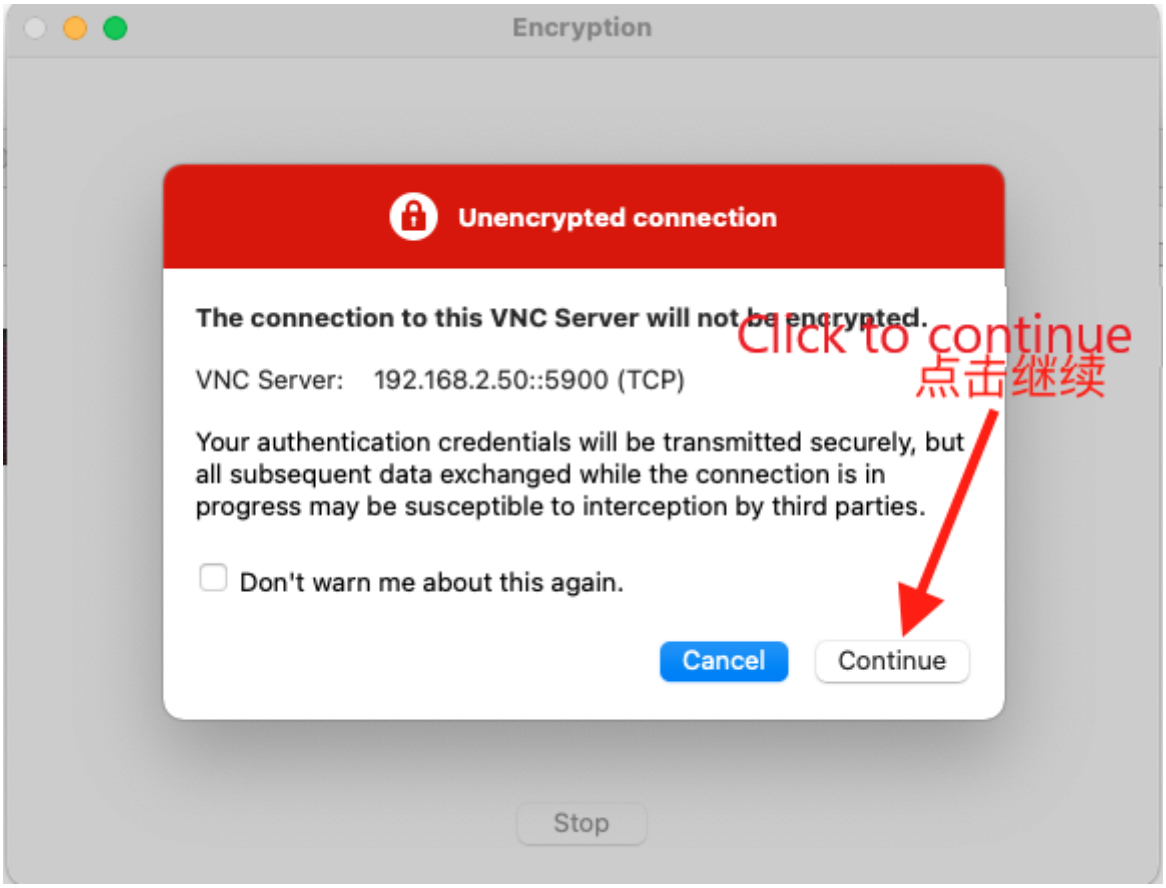
1. Login to robot dog Desktop via vnc viewer

If you have installed the vnc viewer software on your computer.

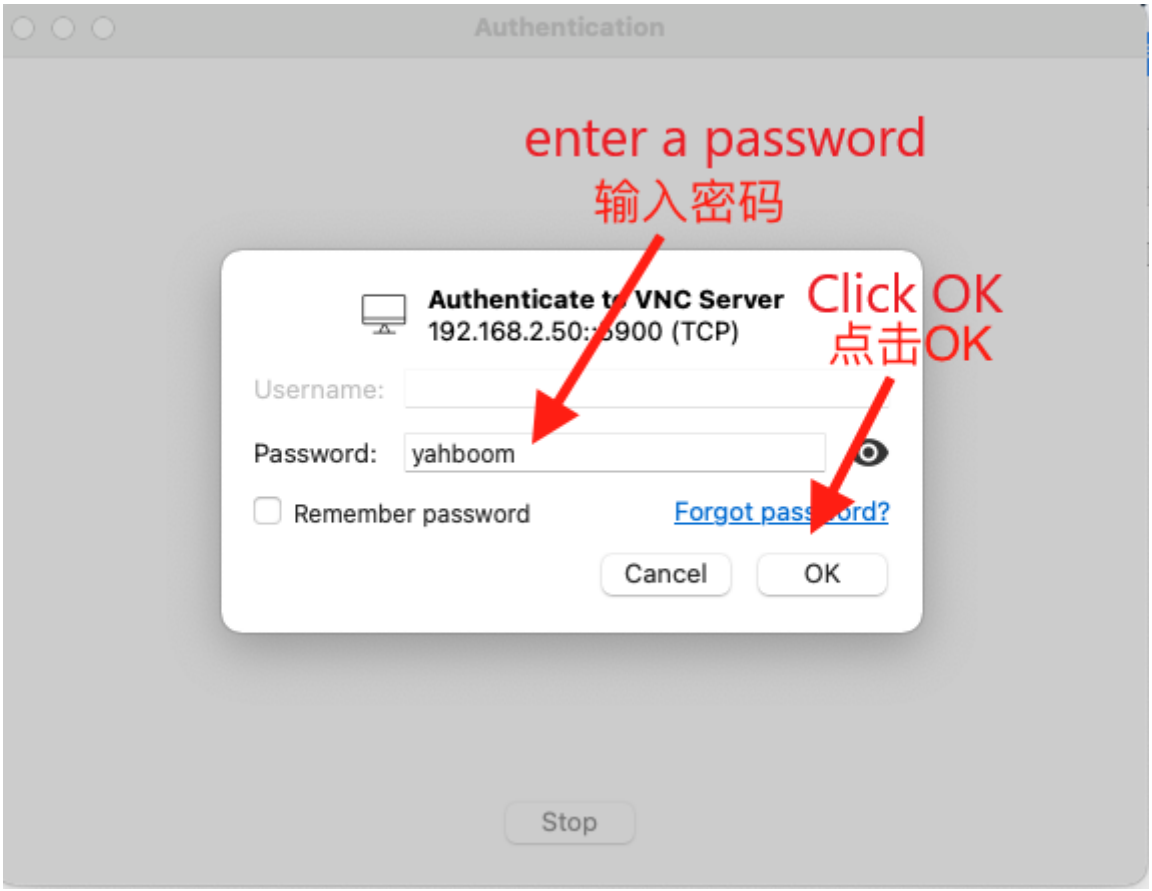
Open vnc viewer, enter the IP address of the robot dog.

The IP address can be viewed at the LCD display of the robot dog.

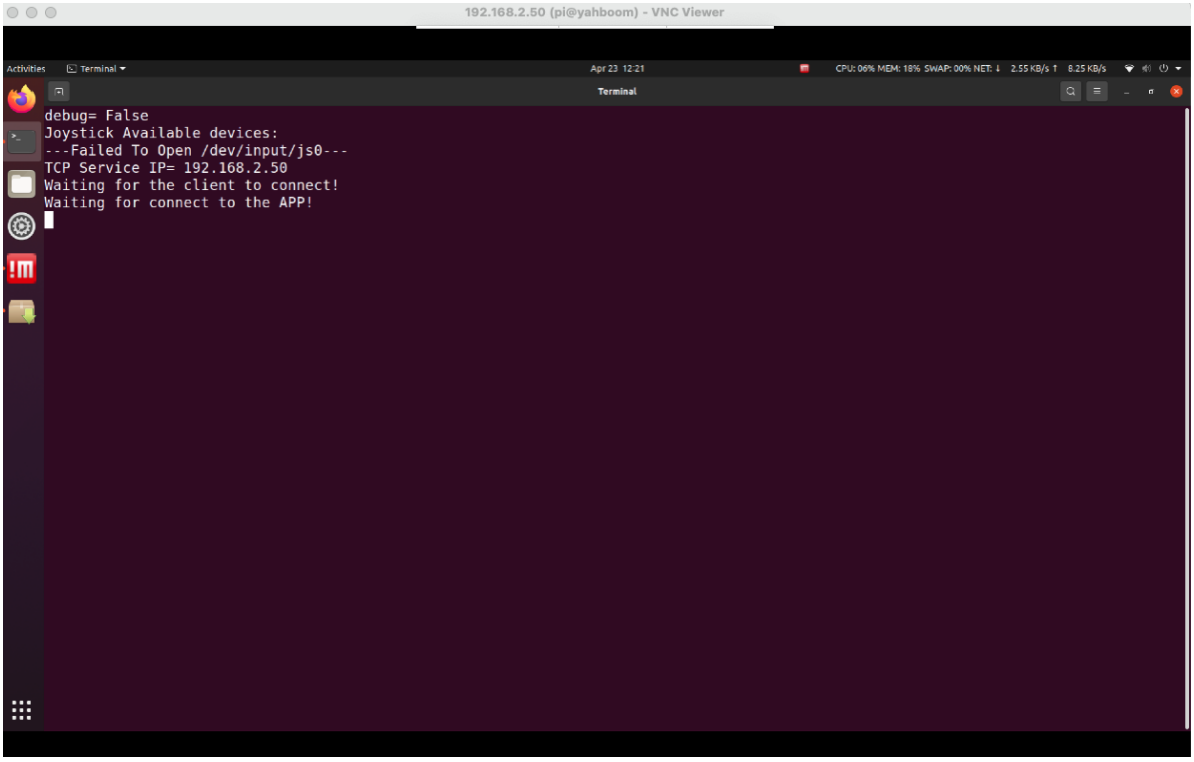
Then press the Enter key and click the Continue button



Enter the robot dog login password: yahboom and click OK.

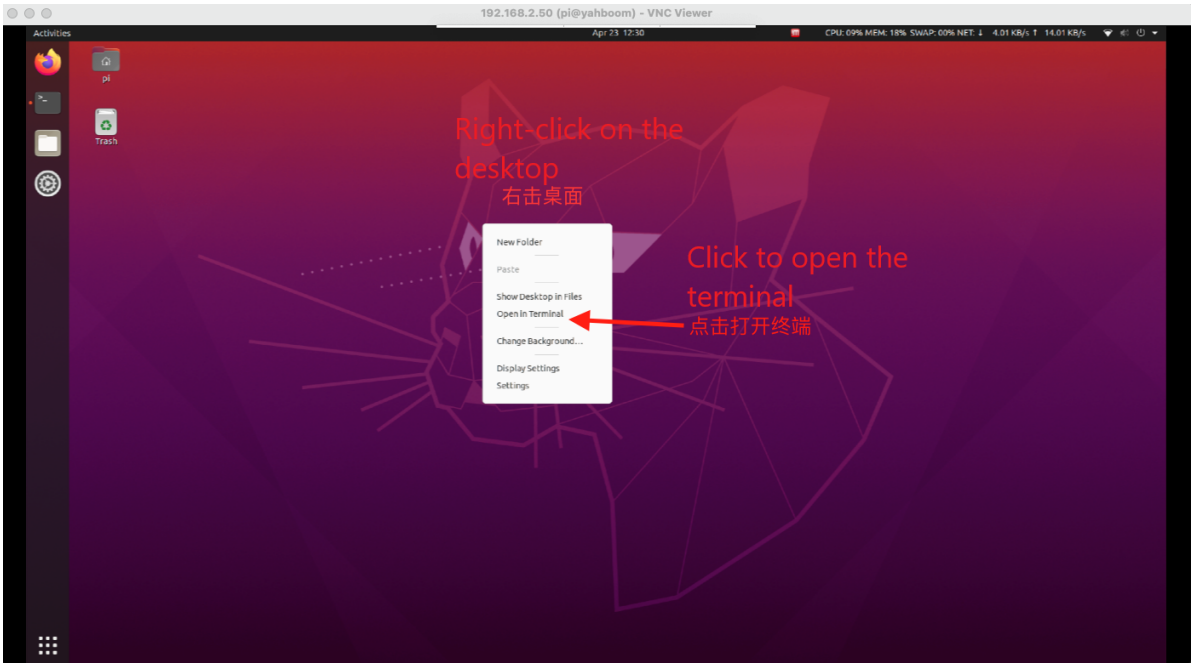


Enter the robot dog operating system.



2. Activate ros2 workspace.

Right click on the desktop and select 'Open in Terminal', open the terminal.



Enter the command in the terminal:

```
cd ~/cartographer_ws
```

```
source install/setup.bash
```

At this point we have activated the workspace.

3. Activate the robot dog status node

You can restart the chassis node, which normally starts automatically. The command to restart the chassis node is:

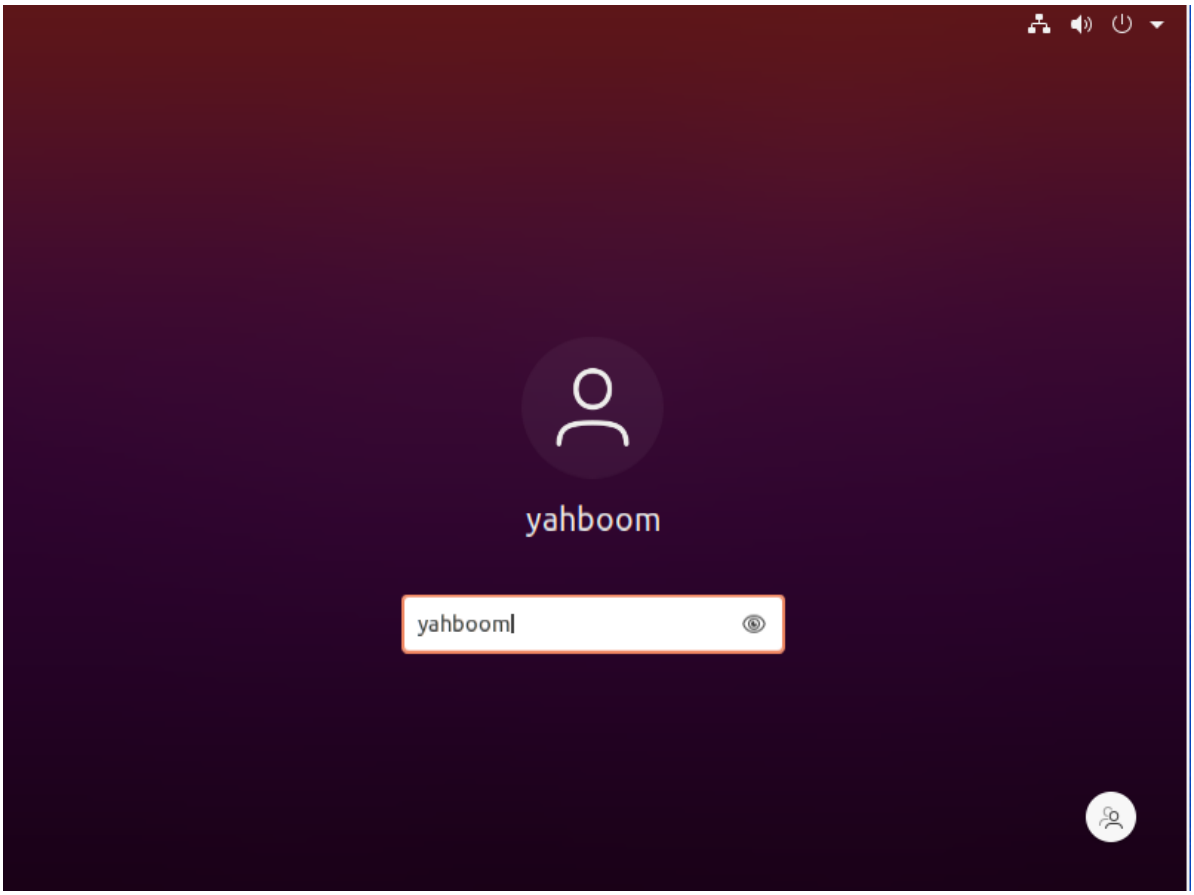
```
sudo systemctl restart YahboomStart.service
```

4. Check the status of robot dog in VM rviz2.

Here to note a robot dog image default open LAN communication ID is 16, at this time to check the virtual machine ROS_DOMAIN_id is not equal to 16. view method:

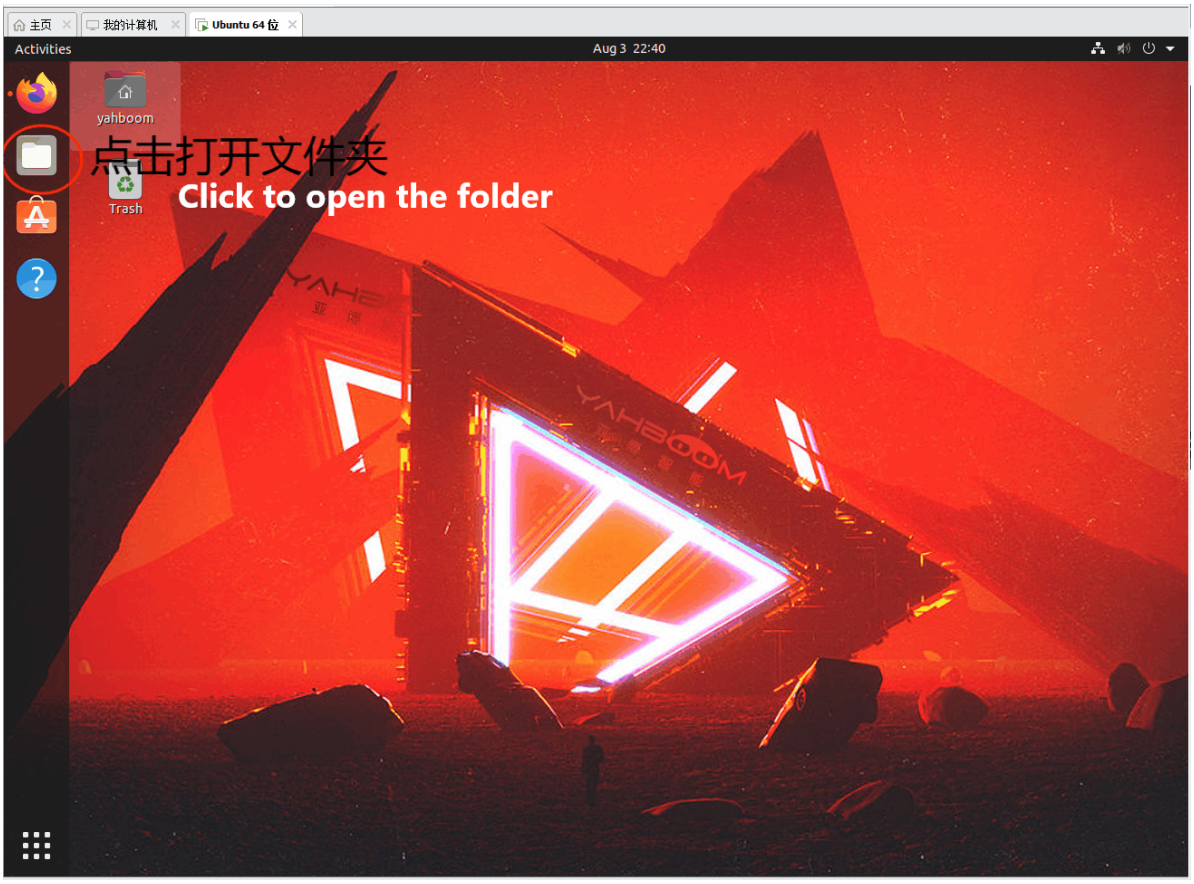
Note: Here the default virtual machine has been installed.

Open the virtual machine, enter the password: yahboom and press enter to enter the system desktop.

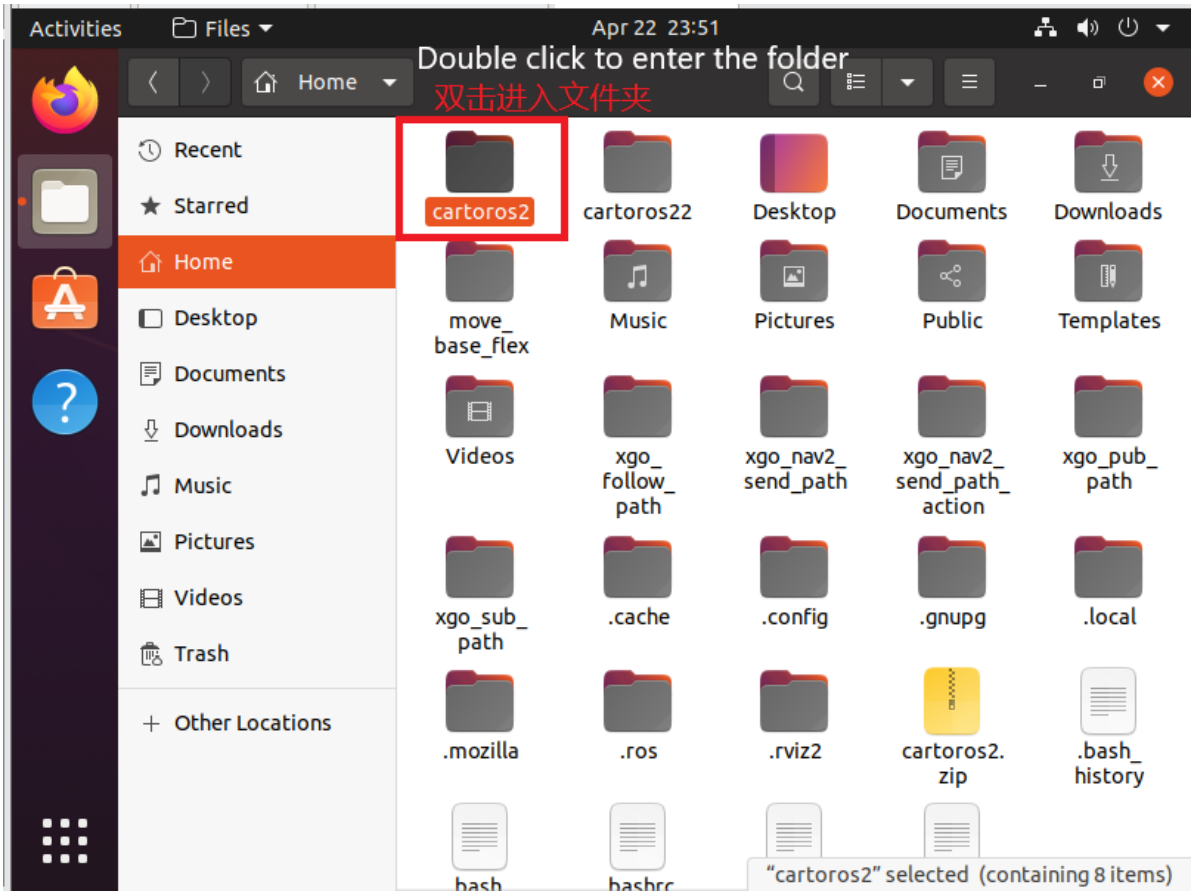


3. Start the robot dog build node

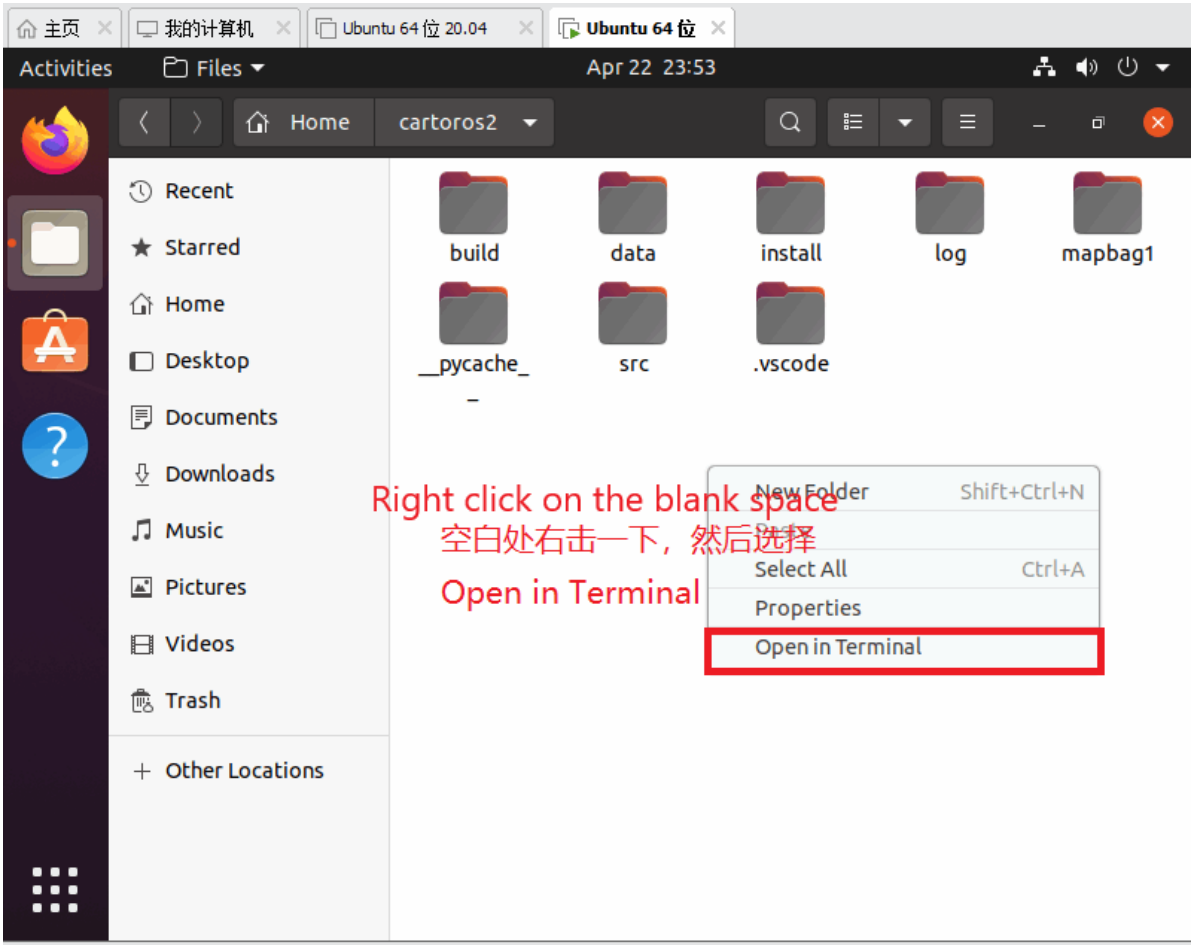
Go to the desktop system and open the folder.



Then double click on the cartoros2 folder



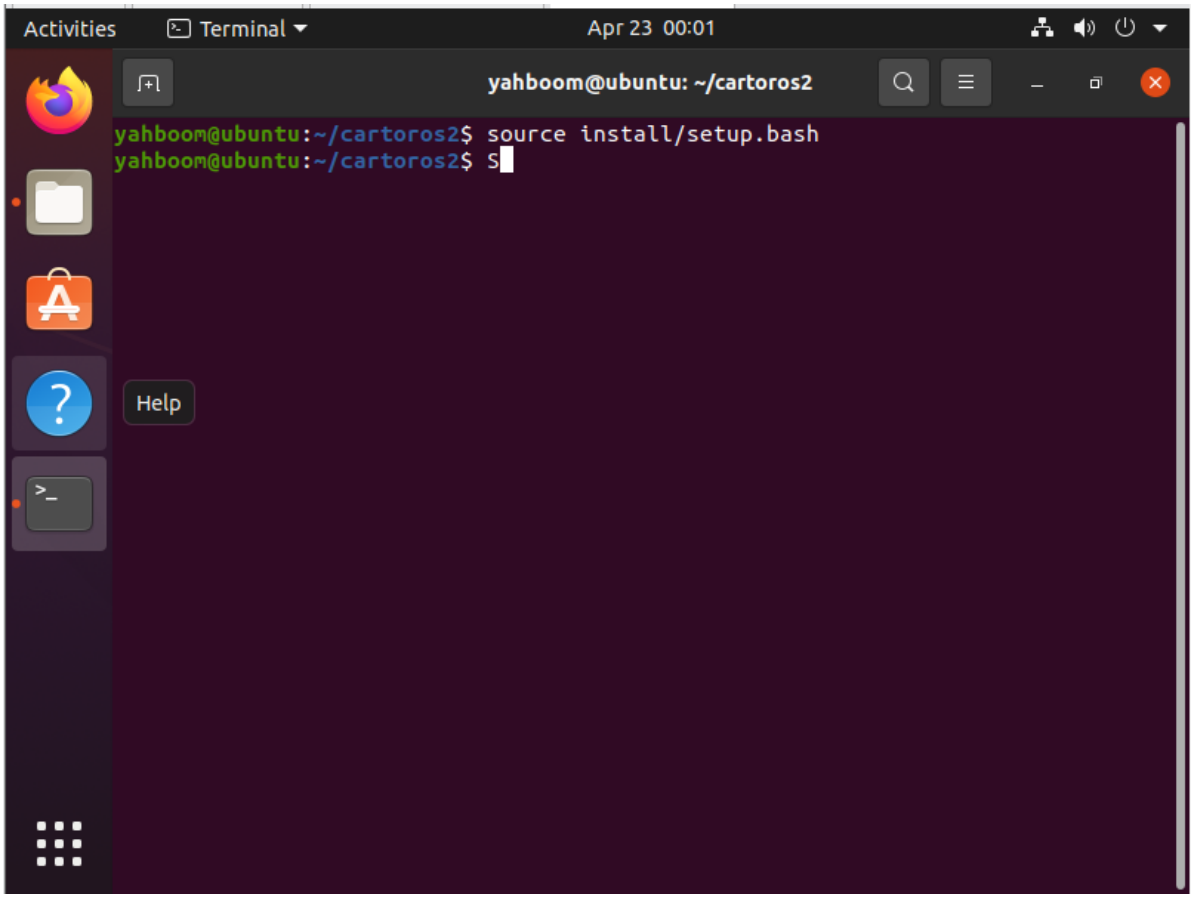
Then right-click in a blank space in the folder and select Open in Terminal



Then activate the environment by typing the following command in the terminal

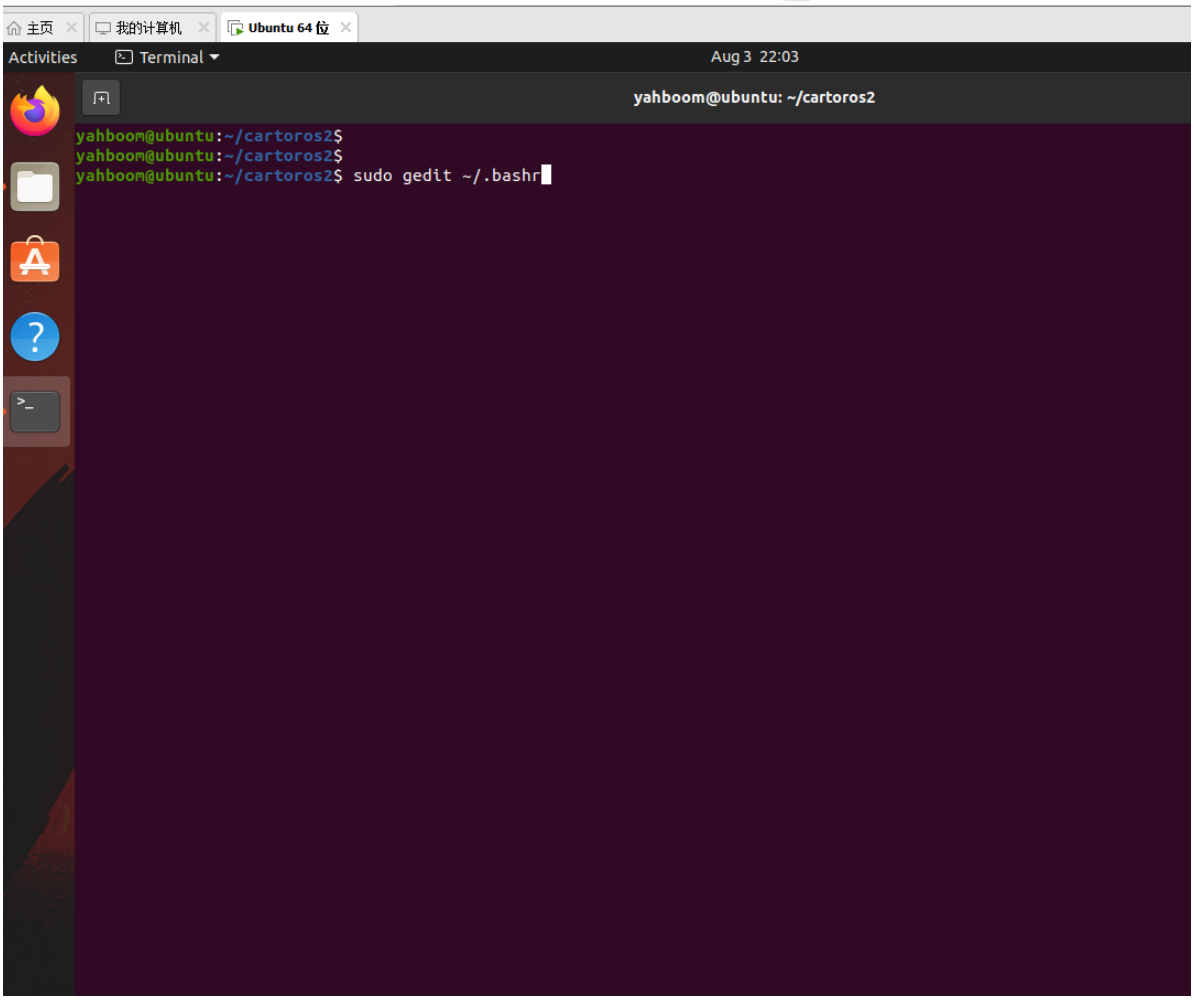
```
source install/setup.bash
```

Press the Enter key when you have finished typing.

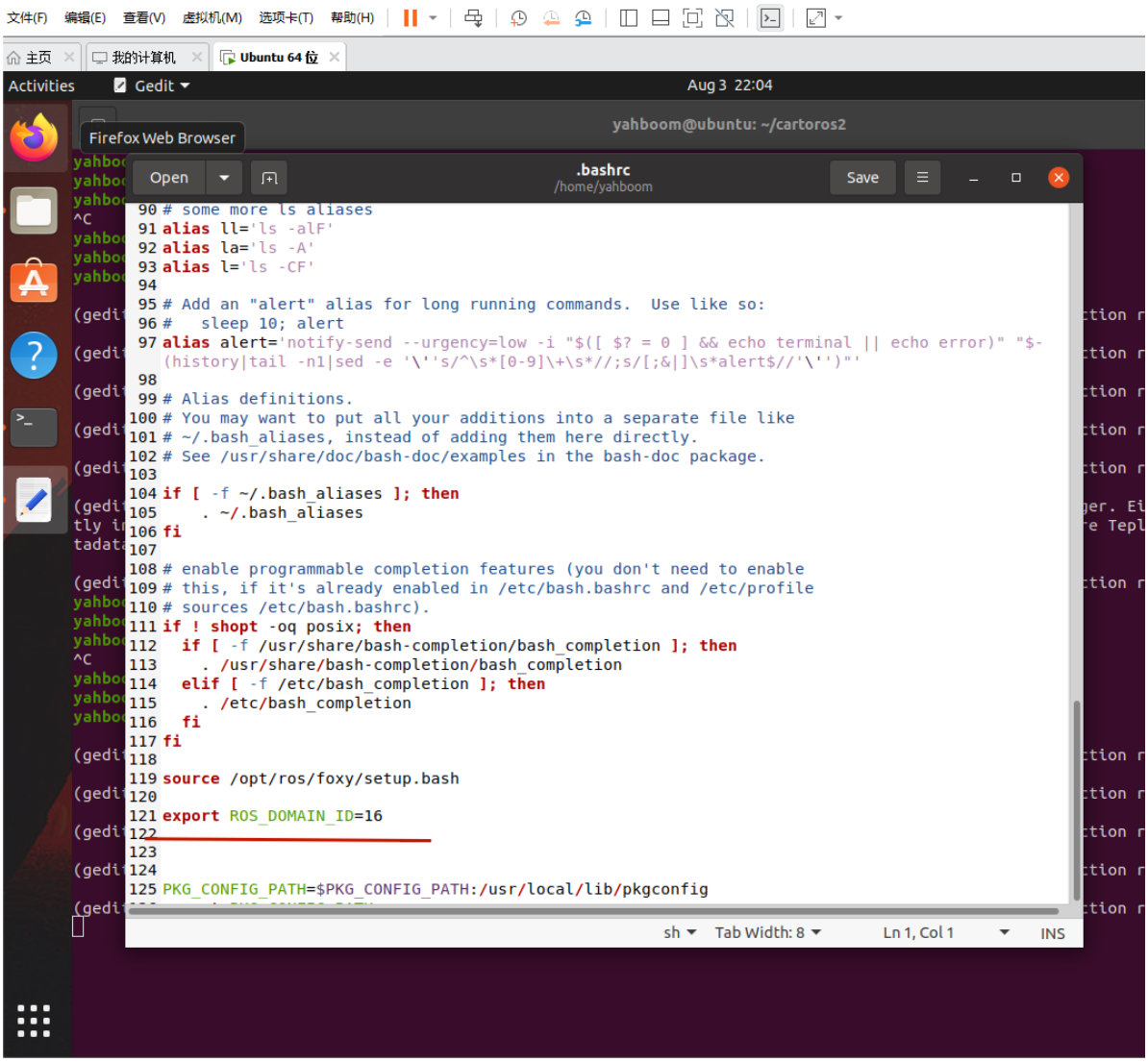


Then enter the command.

```
sudo gedit ~/.bashrc
```



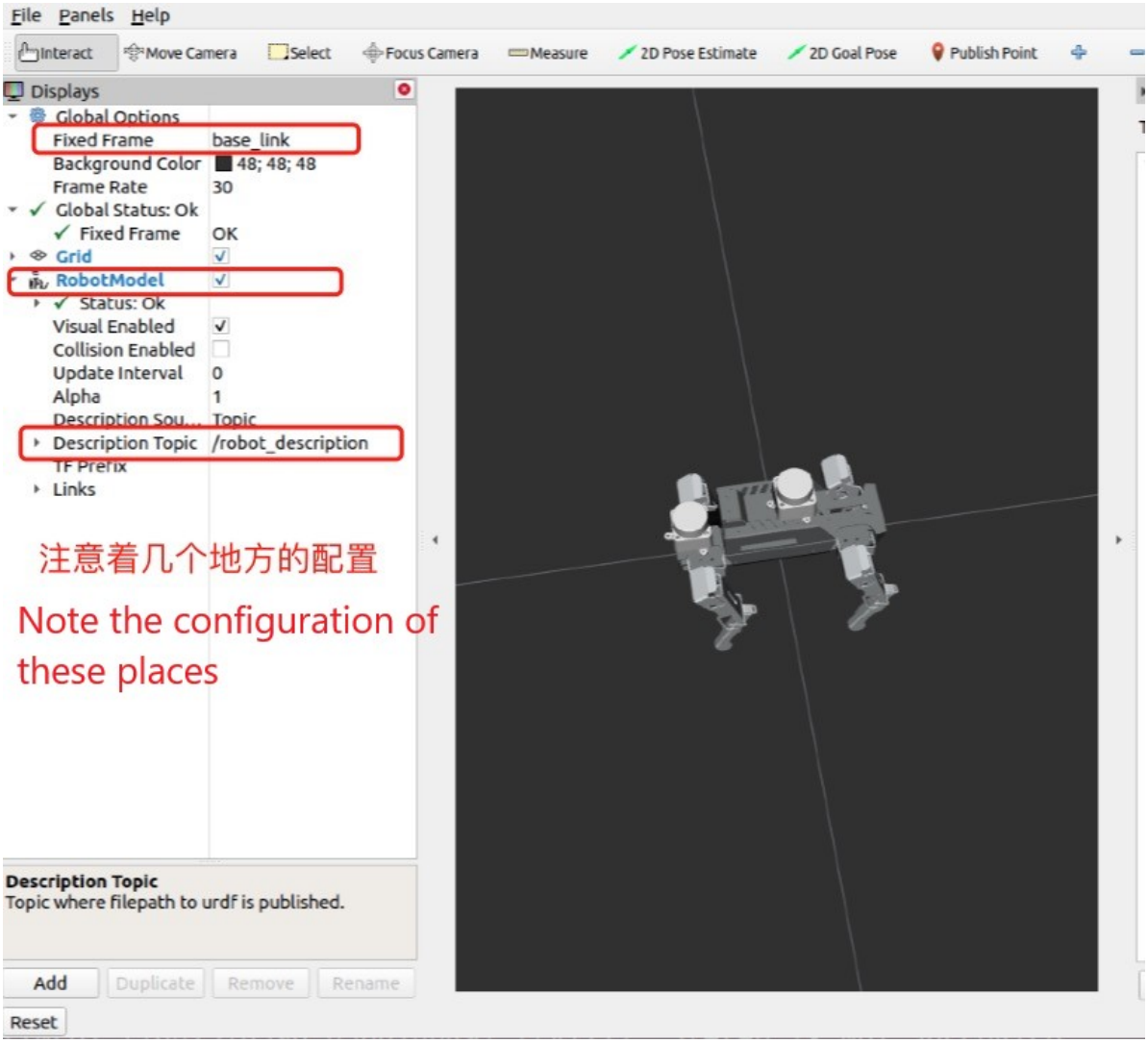
Press enter and take a look at the configuration below in the documentation.



Close the document if it is correct. Type in the terminal:

```
rviz2
```

Press the Enter key and you can see the current status of the robot dog. As shown in the figure below:


File Panels Help
Interact
Move Camera
Select
Focus Camera
Measure
2D Pose Estimate
2D Goal Pose
Publish Point
Displays
Global Options
Fixed Frame base_link
Background Color 48; 48; 48
Frame Rate 30
Global Status: Ok
Fixed Frame OK
Grid
RobotModel
Status: Ok
Visual Enabled
Collision Enabled
Update Interval 0
Alpha 1
Description Sou... Topic
Description Topic /robot_description
TF Prefix
Links
注意着几个地方的配置
Note the configuration of these places
Description Topic
Topic where filepath to urdf is published.
Add
Duplicate
Remove
Rename
Reset