Preparation

1、Install drive

In the provided source package, unzip oradar_ros.zip to get the oradar_ro folder, which is the source code of the ros function package. Enter this function package, there is an sdk folder inside, which stores the driver files of the radar, we open the terminal input in this folder

```
mkdir bulid
cd build
cmake ..
make -j4
sudo make install
```

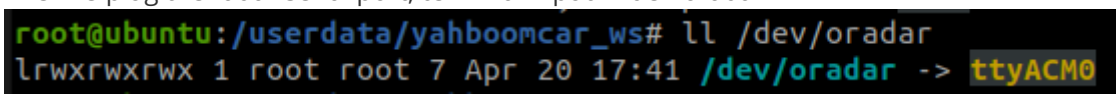
If no error is reported during operation, it means that the driver is successfully installed.

2、Bind lidar port name

Open the terminal under the oradar_ros function package, enter the following command, and copy the oradar.rules file under the function package to /etc/udev/rules.d ,

```
sudo cp oradar.rules /etc/udev/rules.d/
```

Then re-plug the radar serial port, terminal input ll /dev/oradar



If the above content appears, it means that the binding is successful, and the ending is not necessarily 0, and it will change according to the order in which the devices are inserted.

3、Create a new workspace and compile a function package

For example, to create an oradar_ws workspace name, enter in the terminal ,

```
mkdir oradar_ws
cd oradar_ws
mkdir src
cd src
catkin_init_workspace
```

Then copy the decompressed oradar_ros to the oradar_ws/src directory, and then use catkin_make to compile in the oradar_ws directory

```
cd oradar_ws
catkin_make
```

After the compilation is passed, add the path of the workspace to .bashrc

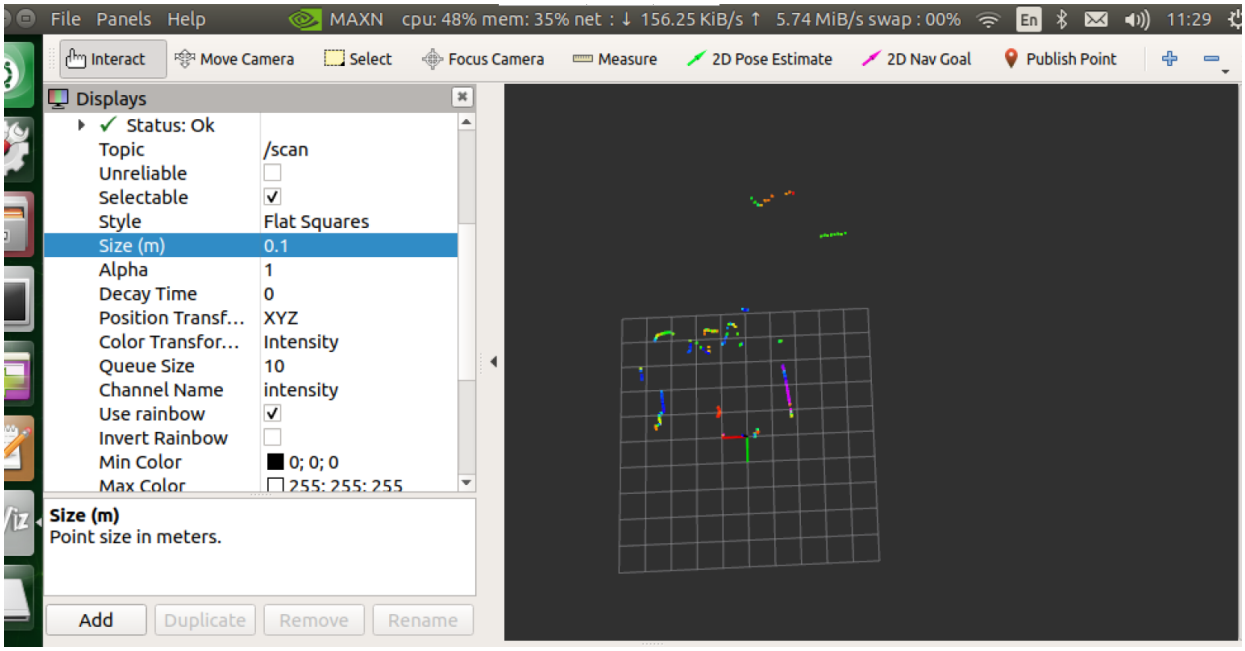
```
sudo gedit ~/.bashrc
```

Copy the following content to the end of the file, ,

```
source ~/oradar_ws/devel/setup.bash --extend
```

Save and exit, reopen a terminal, enter the following command to open the radar and display it in rviz.

```
roslaunch oradar_lidar ms200_scan_view.launch
```



If the above picture appears, it means that all preparations are completed.