Preparation

1.1Compile function package

Unzip oradar_ros-dev-ros2 in the [Source Code] folder to get the oradar_ros-dev-ros2 function package. Copy oradar_ros to the src directory of the workspace you created. Here, the workspace name is oradar_ws as an example. The path of oradar_ws is in the ~ directory, and then return to the workspace directory to compile.

```
cd ~/oradar_ws
colcon build --symlink-install
```

The above screen description appears and the compilation is passed.

Then enter the following command to set the environment variables.

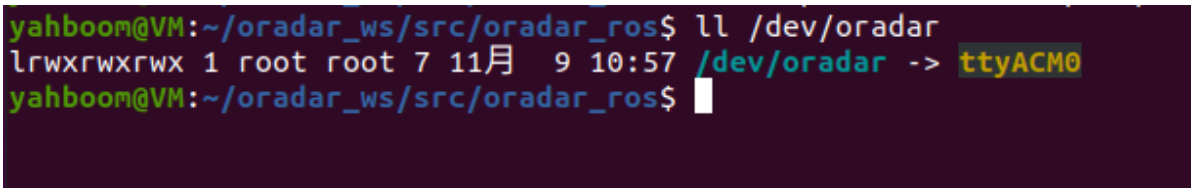
```
echo "source ~/oradar_ws/install/setup.bash --extend" >> ~/.bashrc
```

Open the terminal under the oradar_ros-dev-ros2 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.

Input following command:



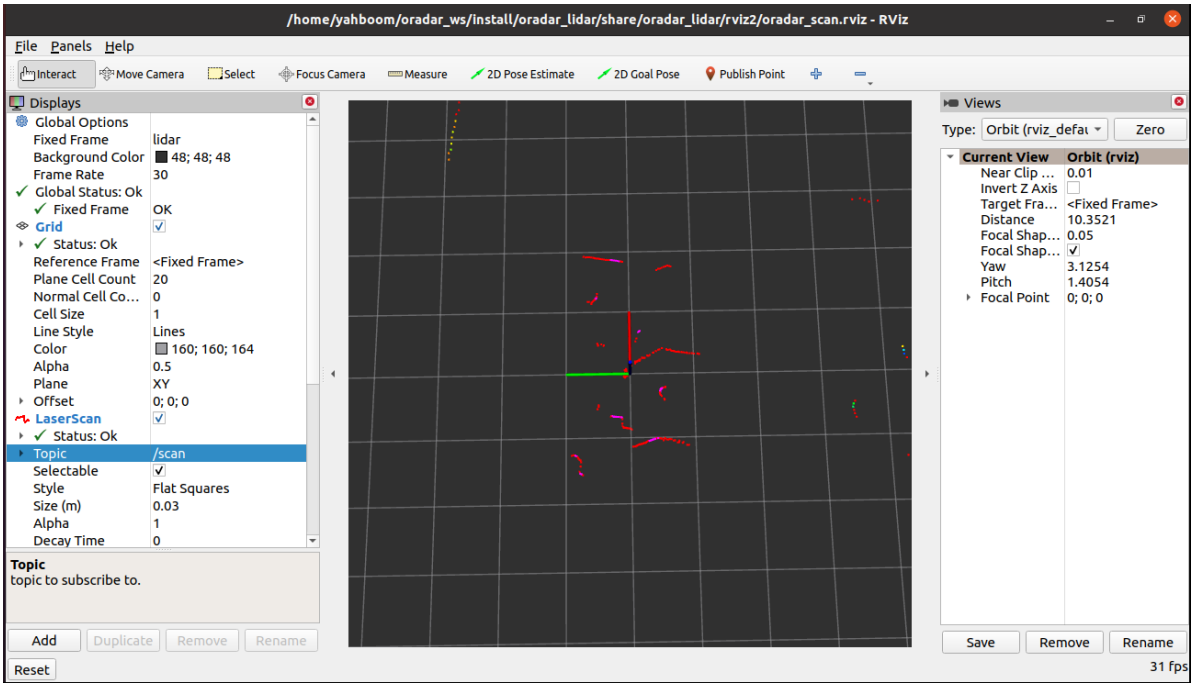
The above content indicates that the binding is successful.

The end is not necessarily 0 and changes according to the order in which the devices are inserted.

1.2 Run launch

Run lidar:

```
ros2 launch oradar_lidar ms200_scan_view.launch.py
```



Lidar node data can be viewed through the following command.

```
ros2 topic echo /scan
```

```
---
header:
  stamp:
    sec: 1699498981
    nanosec: 57374624
  frame_id: lidar
angle_min: 0.0013965616235509515
angle_max: 6.2732367515563965
angle_increment: 0.013937423005700111
time_increment: 0.00022122383234091103
scan_time: 0.09955072402954102
range_min: 0.05000000074505806
range_max: 20.0
ranges:
- 0.1379999965429306
- 0.1420000046491623
- 0.15299999713897705
- 0.0
- 1.8359999656677246
- 1.8450000286102295
- 1.8459999561309814
- 1.8580000400543213
- 1.86899995803833
- 1.871999979019165
- 1.875
- 1.8839999437332153
- 1.8930000066757202
- 1.902999997138977
- 1.9149999618530273
- 1.9220000505447388
- 1.9299999475479126
- 1.944000005722046
- 1.9529999494552612
```