Preparation

1. Install drive

In the provided source code package, unzip oradar_ros.zip to get the oradar_ros folder.

This folder is the source code of the ros function package. When you enter this function package, there is an sdk folder inside, which contains the lidar driver files.

In this folder, we open the terminal and input following command:

```
mkdir bulid
cd build
cmake ..
make -j4
sudo make install
```
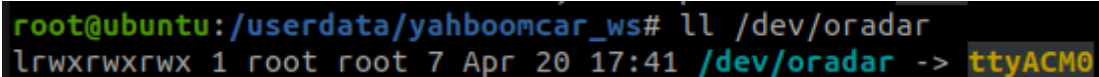
If the system does not prompt any errors, the driver is successfully installed.

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 lidar wiring and enter the command ll /dev/rplidar in the terminal.

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.

3. Create a new workspace and compile function packages

Take the creation name as oradar_ws as an example.

Input following command:

```
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.

Then, in the oradar_ws directory, use catkin_make to compile,

```
cd oradar_ws
catkin_make
```

After the compilation is passed, add the path of the workspace to .bashrc.
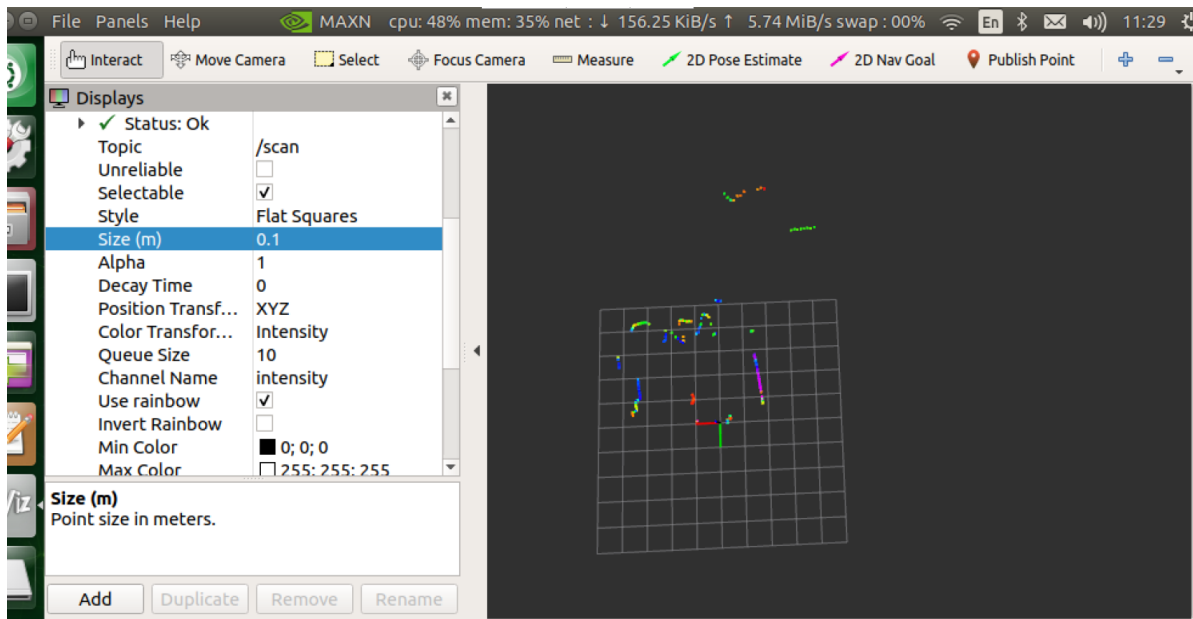
```
sudo gedit ~/.bashrc
```

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 statement, open the radar and display it in rviz.

```
roslaunch oradar_lidar ms200_scan_view.launch
```


When the above screen appears, it means that all preparations have been completed.