导航方面:

显示串口: ls -l /dev |grep ttyUSB

串口通信: roslaunch my\_serial\_node Run\_car.launch

导航配置: roslaunch navigation navigation.launch

航点导航: rosrun navigation WayPoints\_Navigation.py

键盘控制: rosrun teleop\_twist\_keyboard teleop\_twist\_keyboard.py

web与ros连接:

roslaunch rosbridge\_server rosbridge\_websocket.launch

坐标变换：rosrun tf2\_web\_republisher tf2\_web\_republisher

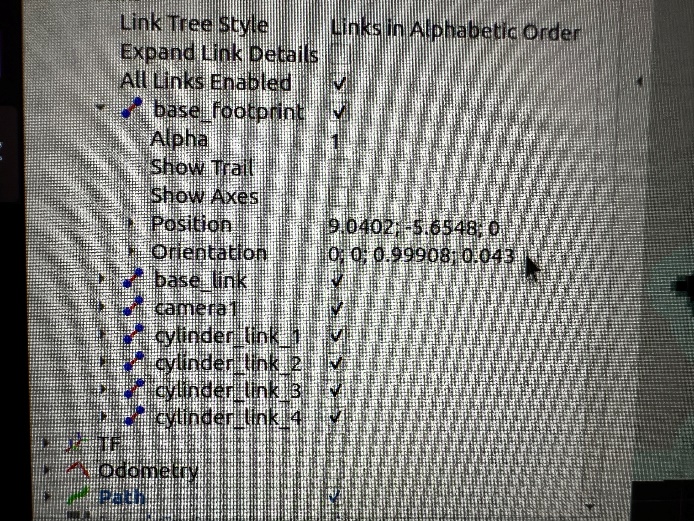
视频流：rosrun web\_video\_server web\_video\_server

web\_rviz:node server.js

机器视觉：

颜色识别：roslaunch robot\_vision color\_detection.launch

缺陷检测：roslaunch robot\_vision defection.launch

**起始点设置如图：**

